Activity Report 2018

Section Software

CEDAR Project-Team

6. New Software and Platforms

6.1. Tatooine

KEYWORDS: RDF - JSon - Knowledge database - Databases - Data integration - Polystore

FUNCTIONAL DESCRIPTION: Tatooine allows to jointly query data sources of heterogeneous formats and data models (relations, RDF graphs, JSON documents etc.) under a single interface. It is capable of evaluating conjunctive queries over several such data sources, distributing computations between the underlying single-data model systems and a Java-based integration layer based on nested tuples.

- Participants: François Goasdoué, Ioana Manolescu, Javier Letelier Ruiz, Michaël Thomazo, Oscar Santiago Mendoza Rivera, Raphael Bonaque, Swen Ribeiro, Tien Duc Cao and Xavier Tannier
- Contact: Ioana Manolescu

6.2. AIDES

KEYWORDS: Data Exploration - Active Learning

FUNCTIONAL DESCRIPTION: AIDES is a data exploration software. It allows a user to explore a huge (tabular) dataset and discover tuples matching his or her interest. Our system repeatedly proposes the most informative tuples to the user, who must annotate them as "interesting" / "not-interesting", and as iterations progress an increasingly accurate model of the user's interest region is built. Our system also focuses on supporting low selectivity, high-dimensional interest regions.

- Contact: Yanlei Diao

6.3. OntoSQL

KEYWORDS: RDF - Semantic Web - Querying - Databases

FUNCTIONAL DESCRIPTION: OntoSQL is a tool providing three main functionalities: - Loading RDF graphs (consisting of data triples and possibly a schema or ontology) into a relational database, - Saturating the data based on the ontology. Currently, RDF Schema ontologies are supported. - Querying the loaded data using conjunctive queries. Data can be loaded either from distinct files or from a single file containing them both. The loading process allows to choose between two storage schemas: - One triples table. - One table per role and concept. Querying provides an SQL translation for each conjunctive query according to the storage schema used in the loading process, then the SQL query is evaluated by the underlying relational database.

- Participants: Ioana Manolescu, Michaël Thomazo and Tayeb Merabti
- Partner: Université de Rennes 1
- Contact: Ioana Manolescu
- URL: https://ontosql.inria.fr/

6.4. ConnectionLens

KEYWORDS: Data management - Big data - Information extraction - Semantic Web

FUNCTIONAL DESCRIPTION: ConnectionLens treats a set of heterogeneous, independently authored data sources as a single virtual graph, whereas nodes represent fine-granularity data items (relational tuples, attributes, key-value pairs, RDF, JSON or XML nodes. . .) and edges correspond either to structural connections (e.g., a tuple is in a database, an attribute is in a tuple, a JSON node has a parent. . .) or to similarity (sameAs) links. To further enrich the content journalists work with, we also apply entity extraction which enables to detect the people, organizations etc. mentioned in text, whether full-text or text snippets found e.g. in RDF or XML. ConnectionLens is thus capable of finding and exploiting connections present across heterogeneous data sources without requiring the user to specify any join predicate.

- Contact: Manolescu Ioana
- Publication: ConnectionLens: Finding Connections Across Heterogeneous Data Sources

6.5. INSEE-Extract

Spreadsheets extractor
KEYWORDS: RDF - Data extraction
FUNCTIONAL DESCRIPTION: Extract content of spreadsheets automatically and store it as RDF triples

- Participants: Ioana Manolescu, Xavier Tannier and Tien Duc Cao
- Contact: Tien Duc Cao
- Publication: Extracting Linked Data from statistic spreadsheets
- URL: https://gitlab.inria.fr/cedar/excel-extractor

6.6. INSEE-Search

KEYWORDS: Document ranking - RDF
FUNCTIONAL DESCRIPTION: Searching for relevant data cells (or data row/column) given a query in natural language (French)

- Participants: Ioana Manolescu, Xavier Tannier and Tien Duc Cao
- Contact: Tien Duc Cao
- Publications: Extracting Linked Data from statistic spreadsheets - Searching for Truth in a Database of Statistics

6.7. RDFQuotient

Quotient summaries of RDF graphs
KEYWORDS: RDF - Graph algorithmics - Graph visualization - Graph summaries - Semantic Web
FUNCTIONAL DESCRIPTION: RDF graphs can be large and heterogeneous, making it hard for users to get acquainted with a new graph and understand whether it may have interesting information. To help users figure it out, we have devised novel equivalence relations among RDF nodes, capable of recognizing them as equivalent (and thus, summarize them together) despite the heterogeneity often exhibited by their incoming and outgoing node properties. From these relations, we derive four novel summaries, called Weak, Strong, Typed Weak and Typed Strong, and show how to obtain from them compact and enticing visualizations.

- Partner: Université de Rennes 1
- Contact: Manolescu Ioana
- Publications: Compact Summaries of Rich Heterogeneous Graphs - Structural Summarization of Semantic Graphs

GRAPHIK Project-Team

6. New Software and Platforms

6.1. Cogui

KEYWORDS: Knowledge database - Ontologies - GUI (Graphical User Interface)

SCIENTIFIC DESCRIPTION: Cogui is a visual tool for building and verifying graphical knowledge bases (KB). Knowledge bases are represented under graphical form (close to conceptual graphs). There is a complete correspondence with the logical existential rule (or Datalog+) framework.

FUNCTIONAL DESCRIPTION: Cogui is a freeware written in Java. It allows to graphically create a KB, to handle its structure and content, and to control it. Currently, it supports Conceptual Graphs and import/export in RDFS and Datalog+. Wizards allow to analyze and check facts with respect to some constraints, as well as to query them while taking into account inferences enabled by the ontology.

RELEASE FUNCTIONAL DESCRIPTION: Plugin-extensible architecture, multi-project management, automatic construction of a web documentation of the ontology, adoption of semantic web conventions (IRIs and namespaces), integration of some Graal functionalities (homomorphisms and OWL 2 import), improvement of the import/export between Cogui knowledge bases and Graal dlgp format.

NEWS OF THE YEAR: Release of a new version (V3) resulting from heavy refactoring to benefit from NetBeans plugin-extensible platform architecture and graphical libraries (total replacement of the graphical editors).

This new version requires to completely revise the user documentation, which is in progress.

- Participants: Alain Gutierrez, Michel Chein, Marie-Laure Mugnier, Michel Leclère and Madalina Croitoru
- Partner: LIRMM
- Contact: Michel Chein
- URL: http://www.lirmm.fr/cogui/

6.2. DAGGER

KEYWORDS: Graph algorithmics - Logic programming

FUNCTIONAL DESCRIPTION: We introduce DAGGER: a generator for logic based argumentation frameworks instantiated from inconsistent knowledge bases expressed using Datalog. The tool allows to import a knowledge base in DLGP format and the generation and visualisation of the corresponding argumentation graph. Furthermore, the argumentation framework can also be exported in the Aspartix format.

- Contact: Madalina Croitoru
- URL: http://www.lirmm.fr/~yun/tools.html

6.3. Eldr

Existential Logic for Defeasible Reasoning

KEYWORDS: Knowledge representation - Logic programming

FUNCTIONAL DESCRIPTION: Eldr is an open source defeasible reasoning tool that allows the use of different semantics (ambiguity blocking/propagating with or without team defeat) in order to reason with incoherent or inconsistent knowledge. It allows the reasoning about preferences and their justification between different agents with a final aim of producing justified preferences on different outcomes (alternatives). These preferences are then used with a voting module (given certain voting strategy) to break ties and establish the chosen alternative. It is applied within the GLOPACK and NOAW projects.

- Contact: Madalina Croitoru
- URL: https://github.com/hamhec/graal-elder

6.4. GRAAL

KEYWORDS: Knowledge database - Ontologies - Querying - Data management

SCIENTIFIC DESCRIPTION: Graal is a Java toolkit dedicated to querying knowledge bases within the framework of existential rules, aka Datalog+/-.

FUNCTIONAL DESCRIPTION: Graal has been designed in a modular way, in order to facilitate software reuse and extension. It should make it easy to test new scenarios and techniques, in particular by combining algorithms. The main features of Graal are currently the following: (1) a data layer that provides generic interfaces to store various kinds of data and query them with (union of) conjunctive queries, currently: MySQL, PostgreSQL, Sqlite, in memory graph and linked list structures, (2) an ontological layer, where an ontology is a set of existential rules, (3) a knowledge base layer, where a knowledge base is composed of a fact base (abstraction of the data via generic interfaces) and an ontology, (4) algorithms to process ontology-mediated queries, based on query rewriting and/or forward chaining (or chase), (5) a rule analyzer, which performs a syntactic and structural analysis of an existential rule set, (6) several IO formats, including imports from OWL 2.

RELEASE FUNCTIONAL DESCRIPTION: Version 1.3.0 (2017) fixes some bugs, makes the dlgp parser more flexible (dlgp being our serialization format for existential rules) and improves the efficiency of the forward chaining (chase) algorithms.

Version 1.3.1 (2018) provides minor optimizations and small bug fixes.

NEWS OF THE YEAR: 2018: Version 1.3.1, with small bug fixes and minor improvements. Several new functionalities were developed by internships in 2018 but the code is not integrated to Graal yet. 2017: New stable version (1.3.0) realised. Moreover, Graal website has been deeply restructured and enriched with new tools, available online or for download, and documentation including tutorials, examples of use, and technical documentation about all Graal modules.

- Participants: Marie-Laure Mugnier, Clément Sipieter, Jean-François Baget, Mélanie König, Michel Leclère and Swan Rocher
- Contact: Marie-Laure Mugnier
- Publications: Graal: A Toolkit for Query Answering with Existential Rules - Datalog+, RuleML and OWL 2: Formats and Translations for Existential Rules
- URL: https://github.com/graphik-team

<div align="center">

LACODAM Project-Team

</div>

6. New Software and Platforms

6.1. REMI

Mining Intuitive Referring Expressions in Knowledge Bases
KEYWORDS: RDF - Knowledge database - Referring expression
FUNCTIONAL DESCRIPTION: REMI takes an RDF knowledge base stored as an HDT file, and a set of target entities and returns a referring expression that is intuitive, i.e., the user is likely to understand it.

- Contact: Luis Galarraga Del Prado

- URL: http://gitlab.inria.fr/lgalarra/remi

6.2. HIPAR

Hierarchical Interpretable Pattern-aided Regression
KEYWORDS: Regression - Pattern extraction
FUNCTIONAL DESCRIPTION: Given a (tabular) dataset with categorical and numerical attributes, HIPAR is a Python library that can extract accurate hybrid rules that offer a trade-off between (a) interpretability, (b) accuracy, and (c) data coverage.

- Contact: Luis Galarraga Del Prado

- URL: https://gitlab.inria.fr/opelgrin/hipar

6.3. NegPSpan

Negative pattern mining with PrefixSpan
KEYWORDS: Pattern discovery - Data mining - Sequential patterns - Traces
SCIENTIFIC DESCRIPTION: Mining frequent sequential patterns consists in extracting recurrent behaviors, modeled as patterns, in a big sequence dataset. Such patterns inform about which events are frequently observed in sequences, i.e. what does really happen. Sometimes, knowing that some specific event does not happen is more informative than extracting a lot of observed events. Negative sequential patterns (NSP) formulate recurrent behaviors by patterns containing both observed events and absent events. Few approaches have been proposed to mine such NSPs. In addition, the syntax and semantics of NSPs differ in the different methods which makes it difficult to compare them. This article provides a unified framework for the formulation of the syntax and the semantics of NSPs. Then, we introduce a new algorithm, NegPSpan, that extracts NSPs using a PrefixSpan depth-first scheme and enabling maxgap constraints that other approaches do not take into account. The formal framework allows for highlighting the differences between the proposed approach wrt to the methods from the literature, especially wrt the state of the art approach eNSP. Intensive experiments on synthetic and real datasets show that NegPSpan can extract meaningful NSPs and that it can process bigger datasets than eNSP thanks to significantly lower memory requirements and better computation times.
FUNCTIONAL DESCRIPTION: NegPSpan is software to extract patterns from sequential data (traces, sequences of events, client pathways, etc.). The NegPSpan software extracts two types of patterns: the classical sequential patterns and the negative sequential patterns. Sequential patterns describe recurrent behaviors described as a sequence of events (e.g. event A occurs, then event B occurs and finally C occurs) while negative sequential patterns hold information about absent event (e.g. event A occurs, then event B occurs but without any C in between).

The user has to provide a dataset in the IBM sequence format and, at least, a parameters corresponding to the minimal number of occurrences in the dataset (and possible additional parameters). The software efficiently extracts the patterns and output them (in a text or JSON format). The software can use different strategies for exploring negative sequential patterns, and also specify some constraints about the expected patterns.

NEWS OF THE YEAR: NegPSpan has been developed in 2018.

- Participants: Thomas Guyet and René Quiniou
- Contact: Thomas Guyet
- Publication: NegPSpan: efficient extraction of negative sequential patterns with embedding constraints
- URL: http://people.irisa.fr/Thomas.Guyet/negativepatterns/evalnegpat.php

LINKS Project-Team

6. New Software and Platforms

6.1. ShEx validator

Validation of Shape Expression schemas

KEYWORDS: Data management - RDF

FUNCTIONAL DESCRIPTION: Shape Expression schemas is a formalism for defining constraints on RDF graphs. This software allows to check whether a graph satisfies a Shape Expressions schema.

RELEASE FUNCTIONAL DESCRIPTION: ShExJava now uses the Commons RDF API and so support RDF4J, Jena, JSON-LD-Java, OWL API and Apache Clerezza. It can parse ShEx schema in the ShEcC, ShEJ, ShExR formats and can serialize a schema in ShExJ.

To validate data against a ShExSchema using ShExJava, you have two different algorithms: - the refine algorithm: compute once and for all the typing for the whole graph - the recursive algorithm: compute only the typing required to answer a validate(node,ShapeLabel) call and forget the results.

- Contact: Iovka Boneva
- URL: http://shexjava.lille.inria.fr/

6.2. gMark

gMark: schema-driven graph and query generation

KEYWORDS: Semantic Web - Data base

FUNCTIONAL DESCRIPTION: gMark allow the generation of graph databases and an associated set of query from a schema of the graph.gMark is based on the following principles: - great flexibility in the schema definition - ability to generate big size graphs - ability to generate recursive queries - ability to generate queries with a desired selectivity

- Contact: Aurélien Lemay
- URL: https://github.com/graphMark/gmark

6.3. SmartHal

KEYWORD: Bibliography

FUNCTIONAL DESCRIPTION: SmartHal is a better tool for querying the HAL bibliography database, while is based on Haltool queries. The idea is that a Haltool query returns an XML document that can be queried further. In order to do so, SmartHal provides a new query language. Its queries are conjunctions of Haltool queries (for a list of laboratories or authors) with expressive Boolean queries by which answers of Haltool queries can be refined. These Boolean refinement queries are automatically translated to XQuery and executed by Saxon. A java application for extraction from the command line is available. On top of this, we have build a tool for producing the citation lists for the evaluation report of the LIFL, which can be easily adapter to other Labs.

- Contact: Joachim Niehren
- URL: http://smarthal.lille.inria.fr/

6.4. QuiXPath

KEYWORDS: XML - NoSQL - Data stream

SCIENTIFIC DESCRIPTION: The QuiXPath tools supports a very large fragment of XPath 3.0. The QuiXPath library provides a compiler from QuiXPath to FXP, which is a library for querying XML streams with a fragment of temporal logic.

FUNCTIONAL DESCRIPTION: QuiXPath is a streaming implementation of XPath 3.0. It can query large XML files without loading the entire file in main memory, while selecting nodes as early as possible.

- Contact: Joachim Niehren
- URL: https://project.inria.fr/quix-tool-suite/

6.5. X-FUN

KEYWORDS: Programming language - Compilers - Functional programming - Transformation - XML

FUNCTIONAL DESCRIPTION: X-FUN is a core language for implementing various XML, standards in a uniform manner. X-Fun is a higher-order functional programming language for transforming data trees based on node selection queries.

- Participants: Joachim Niehren and Pavel Labath
- Contact: Joachim Niehren

<p style="text-align:center">**MAGNET Project-Team**</p>

6. New Software and Platforms

6.1. CoRTeX

Python library for noun phrase COreference Resolution in natural language TEXts

KEYWORD: Natural language processing

FUNCTIONAL DESCRIPTION: CoRTex is a LGPL-licensed Python library for Noun Phrase coreference resolution in natural language texts. This library contains implementations of various state-of-the-art coreference resolution algorithms, including those developed in our research. In addition, it provides a set of APIs and utilities for text pre-processing, reading the CONLL2012 and CONLLU annotation formats, and performing evaluation, notably based on the main evaluation metrics (MUC, B-CUBED, and CEAF). As such, CoRTex provides benchmarks for researchers working on coreference resolution, but it is also of interest for developers who want to integrate a coreference resolution within a larger platform. It currently supports use of the English or French language.

- Participant: Pascal Denis
- Partner: Orange Labs
- Contact: Pascal Denis
- URL: https://gitlab.inria.fr/magnet/CoRTeX

6.2. Mangoes

MAgnet liNGuistic wOrd vEctorS

KEYWORDS: Word embeddings - NLP

FUNCTIONAL DESCRIPTION: Process textual data and compute vocabularies and co-occurrence matrices. Input data should be raw text or annotated text. Compute word embeddings with different state-of-the art unsupervised methods. Propose statistical and intrinsic evaluation methods, as well as some visualization tools.

- Contact: Nathalie Vauquier
- URL: https://gitlab.inria.fr/magnet/mangoes

6.3. metric-learn

KEYWORDS: Machine learning - Python - Metric learning

FUNCTIONAL DESCRIPTION: Distance metrics are widely used in the machine learning literature. Traditionally, practicioners would choose a standard distance metric (Euclidean, City-Block, Cosine, etc.) using a priori knowledge of the domain. Distance metric learning (or simply, metric learning) is the sub-field of machine learning dedicated to automatically constructing optimal distance metrics.

This package contains efficient Python implementations of several popular metric learning algorithms.

- Partner: Parietal
- Contact: William De Vazelhes
- URL: https://github.com/metric-learn/metric-learn

6.4. MyLocalInfo

KEYWORDS: Privacy - Machine learning - Statistics

FUNCTIONAL DESCRIPTION: Decentralized algorithms for machine learning and inference tasks which (1) perform as much computation as possible locally and (2) ensure privacy and security by avoiding personal data leaves devices.

- Contact: Nathalie Vauquier
- URL: https://gitlab.inria.fr/magnet/mylocalinfo

MOEX Project-Team (section vide)

<div align="center">

ORPAILLEUR Project-Team

</div>

6. New Software and Platforms

6.1. ARPEnTAge

Analyse de Régularités dans les Paysages : Environnement, Territoires, Agronomie
KEYWORDS: Stochastic process - Hidden Markov Models
FUNCTIONAL DESCRIPTION: ARPEnTAge is a software based on stochastic models (HMM2 and Markov Field) for analyzing spatio-temporal data-bases. ARPEnTAge is built on top of the CarottAge system to fully take into account the spatial dimension of input sequences. It takes as input an array of discrete data in which the columns contain the annual land-uses and the rows are regularly spaced locations of the studied landscape. It performs a Time-Space clustering of a landscape based on its time dynamic Land Uses (LUS). Displaying tools and the generation of Time-dominant shape files have also been defined.

- Partner: INRA
- Contact: Jean-François Mari
- URL: http://carottage.loria.fr/index_in_english.html

6.2. CarottAge

KEYWORDS: Stochastic process - Hidden Markov Models
FUNCTIONAL DESCRIPTION: The system CarottAge is based on Hidden Markov Models of second order and provides a non supervised temporal clustering algorithm for data mining and a synthetic representation of temporal and spatial data. CarottAge is currently used by INRA researchers interested in mining the changes in territories related to the loss of biodiversity (projects ANR BiodivAgrim and ACI Ecoger) and/or water contamination. CarottAge is also used for mining hydromorphological data. Actually a comparison was performed with three other algorithms classically used for the delineation of river continuum and CarottAge proved to give very interesting results for that purpose.

- Participants: Florence Le Ber and Jean-François Mari
- Partner: INRA
- Contact: Jean-François Mari
- URL: http://carottage.loria.fr/index_in_english.html

6.3. CORON

KEYWORDS: Data mining - Closed itemset - Frequent itemset - Generator - Association rule - Rare itemset
FUNCTIONAL DESCRIPTION: The Coron platform is a KDD toolkit organized around three main components: (1) Coron-base, (2) AssRuleX, and (3) pre- and post-processing modules.

The Coron-base component includes a complete collection of data mining algorithms for extracting itemsets such as frequent itemsets, closed itemsets, generators and rare itemsets. In this collection we can find APriori, Close, Pascal, Eclat, Charm, and, as well, original algorithms such as ZART, Snow, Touch, and Talky-G. AssRuleX generates different sets of association rules (from itemsets), such as minimal non-redundant association rules, generic basis, and informative basis. In addition, the Coron system supports the whole life-cycle of a data mining task and proposes modules for cleaning the input dataset, and for reducing its size if necessary.

- Participants: Adrien Coulet, Aleksey Buzmakov, Amedeo Napoli, Florent Marcuola, Jérémie Bourseau, Laszlo Szathmary, Mehdi Kaytoue, Victor Codocedo and Yannick Toussaint
- Contact: Amedeo Napoli
- URL: http://coron.loria.fr/site/index.php

6.4. LatViz: Visualization of Concept Lattices

- Contact: Amedeo Napoli
- URL: http://latviz.loria.fr/
- KEYWORDS: Formal Concept Analysis, Pattern Structures, Concept Lattice, Implications, Visualization

FUNCTIONAL DESCRIPTION.

LatViz is a tool allowing the construction, the display and the exploration of concept lattices. LatViz proposes some noticeable improvements over existing tools and introduces various functionalities focusing on interaction with experts, such as visualization of pattern structures for dealing with complex non-binary data, AOC-poset which is composed of the core elements of the lattice, concept annotations, filtering based on various criteria and a visualization of implications [70]. This way the user can effectively perform interactive exploratory knowledge discovery as often needed in knowledge engineering.

The LatViz platform can be associated with the Coron platform and extends its visualization capabilities (see http://coron.loria.fr). Recall that the Coron platform includes a complete collection of data mining algorithms for extracting itemsets and association rules.

6.5. OrphaMine: Data Mining Platform for Orphan Diseases

- Contact: Chedy Raïssi
- URL: http://orphamine.inria.fr/
- KEYWORDS: Bioinformatics, data mining, biology, health, data visualization, drug development.

FUNCTIONAL DESCRIPTION.

The OrphaMine platform enables visualization, data integration and in-depth analytics in the domain of "orphan diseases", where data is extracted from the OrphaData ontology (http://www.orpha.net/consor/cgi-bin/index.php). At present, we aim at building a true collaborative portal that will serve different actors: (i) a general visualization of OrphaData data for physicians working, maintaining and developing this knowledge database about orphan diseases. (ii) the integration of analytics (data mining) algorithms developed by the different academic actors. (iii) the use of these algorithms to improve our general knowledge of rare diseases.

6.6. Siren: Interactive and Visual Redescription Mining

- Contact: Esther Catherine Galbrun
- URL: http://siren.gforge.inria.fr/main/
- KEYWORDS: Redescription mining, Interactivity, Visualization.

FUNCTIONAL DESCRIPTION.

Siren is a tool for interactive mining and visualization of redescriptions. Redescription mining aims to find distinct common characterizations of the same objects and, vice versa, to identify sets of objects that admit multiple shared descriptions. The goal is to provide domain experts with a tool allowing them to tackle their research questions using redescription mining. Merely being able to find redescriptions is not enough. The expert must also be able to understand the redescriptions found, adjust them to better match his domain knowledge and test alternative hypotheses with them, for instance. Thus, Siren allows mining redescriptions in an anytime fashion through efficient, distributed mining, to examine the results in various linked visualizations, to interact with the results either directly or via the visualizations, and to guide the mining algorithm toward specific redescriptions.

New features, such as a visualization of the contribution of individual literals in the queries and the simplification of queries as a post-processing, have been added to the tool.

<p align="center" style="color:red">PETRUS Project-Team</p>

6. New Software and Platforms

6.1. PLUG-DB ENGINE

KEYWORDS: Databases - Personal information - Privacy - Hardware and Software Platform

FUNCTIONAL DESCRIPTION: en PlugDB is a complete platform dedicated to a secure and ubiquitous management of personal data. It aims at providing an alternative to a systematic centralization of personal data. The PlugDB engine is a personal database server capable of storing data (tuples and documents) in tables and BLOBs, indexing them, querying them in SQL, sharing them through assertional access control policies and enforcing transactional properties (atomicity, integrity, durability).

The PlugDB engine is embedded in a tamper-resistant hardware device combining the security of smartcard with the storage capacity of NAND Flash. The personal database is hosted encrypted in NAND Flash and the PlugDB engine code runs in the microcontroller. Complementary modules allow to pre-compile SQL queries for the applications, communicate with the DBMS from a remote Java program, synchronize local data with remote servers (typically used for recovering the database in the case of a broken or lost devices) and participate in distributed computation (e.g., global queries). PlugDB runs both on secure devices provided by Gemalto and on specific secure devices designed by PETRUS and assembled by electronic SMEs. Mastering the hardware platform opens up new research and experiment opportunities (e.g., support for wireless communication, secure authentication, sensing capabilities, battery powered ...). PlugDB engine has been registered first at APP (Agence de Protection des Programmes) in 2009 - a new version being registered every two years - and the hardware datasheets in 2015.

PlugDB has been experimented in the field, notably in the healthcare domain. We also recently set up an educational platform on top of PlugDB, named SIPD (Système d'Information Privacy-by-Design) and used at ENSIIE, INSA CVL and UVSQ through the Versailles Sciences Lab fablab, to raise students awareness of privacy protection problems and embedded programming. As a conclusion, PlugDB combines several research contributions from the team, at the crossroads of flash data management, embedded data processing and secure distributed computations. It then strongly federates all members of our team (permanent members, PhD students and engineers). It is also a vector of visibility, technological transfer and dissemination and gives us the opportunity to collaborate with researchers from other disciplines around a concrete privacy-enhancing platform.

PlugDB is now being industrialized in the context of the OwnCare Inria Innovation Lab (II-Lab). In OwnCare, PlugDB acts as a secure personal cloud to manage medical/social data for people receiving care at home. It should be deployed over 10.000 patient in the Yvelines district. The industrialization process covers the development of a complete testing environment, the writing of a detailed documentation and the development of additional features (e.g., embedded ODBC driver, TPM support, flexible access control model and embedded code upgrade notably). It has also required the design of a new hardware platform equipped with a battery power supply, introducing new energy consumption issues for the embedded software.

- Participants: Aydogan Ersoz, Laurent Schneider, Luc Bouganim, Nicolas Anciaux and Philippe Pucheral
- Contact: Nicolas Anciaux
- URL: https://project.inria.fr/plugdb/

<div align="center">

TYREX Project-Team

</div>

5. New Software and Platforms

5.1. SPARQLGX

KEYWORDS: RDF - SPARQL - Distributed computing

SCIENTIFIC DESCRIPTION: SPARQL is the W3C standard query language for querying data expressed in RDF (Resource Description Framework). The increasing amounts of RDF data available raise a major need and research interest in building efficient and scalable distributed SPARQL query evaluators.

In this context, we propose and share SPARQLGX: our implementation of a distributed RDF datastore based on Apache Spark. SPARQLGX is designed to leverage existing Hadoop infrastructures for evaluating SPARQL queries. SPARQLGX relies on a translation of SPARQL queries into executable Spark code that adopts evaluation strategies according to (1) the storage method used and (2) statistics on data. Using a simple design, SPARQLGX already represents an interesting alternative in several scenarios.

FUNCTIONAL DESCRIPTION: This software system is an implementation of a distributed evaluator of SPARQL queries. It makes it possible to evaluate SPARQL queries on billions of triples distributed across multiple nodes in a cluster, while providing attractive performance figures.

RELEASE FUNCTIONAL DESCRIPTION: - Faster load routine which widely improves this phase perfomances by reading once the initial triple file and by partitioning data in the same time into the correct predicate files. - Improving the generated Scala-code of the translation process with mapValues. This technic allows not to break the partitioning of KeyValueRDD while applying transformations to the values instead of the traditional map that was done prior. - Merging and cleaning several scripts in bin/ such as for example sgx-eval.sh and sde-eval.sh - Improving the compilation process of compile.sh - Cleaner test scripts in tests/ - Offering the possibility of an easier deployment using Docker.

- Participants: Damien Graux, Thomas Calmant, Louis Jachiet, Nabil Layaïda and Pierre Genevès
- Contact: Pierre Genevès
- Publications: Optimizing SPARQL query evaluation with a worst-case cardinality estimation based on statistics on the data - The SPARQLGX System for Distributed Evaluation of SPARQL Queries
- URL: https://github.com/tyrex-team/sparqlgx

5.2. musparql

KEYWORDS: SPARQL - RDF - Property paths

FUNCTIONAL DESCRIPTION: reads a SPARQL request and translates it into an internal algebra. Rewrites the resulting term into many equivalent versions, then choses one of them and executes it on a graph.

- Participant: Louis Jachiet
- Contact: Nabil Layaïda
- Publication: Extending the SPARQL Algebra for the optimization of Property Paths
- URL: https://gitlab.inria.fr/tyrex/musparql

5.3. MRB

Mixed Reality Browser

KEYWORDS: Augmented reality - Geolocation - Indoor geolocalisation - Smartphone

FUNCTIONAL DESCRIPTION: MRB displays PoI (Point of Interest) content remotely through panoramics with spatialized audio, or on-site by walking to the corresponding place, it can be used for indoor-outdoor navigation, with assistive audio technology for the visually impaired. It is the only browser of geolocalized data to use XML as a native format for PoIs, panoramics, 3D audio and to rely on HTML5 both for the iconic and full information content of PoIs. Positioning in MRB is based on a PDR library, written in C++ and Java and developed by the team, which provides the user's location in real time based on the interpretation of sensors. Three main modules have been designed to build this positioning system: (i) a pedometer that estimates the distance the user has walked and his speed, (ii) a motion manager that enables data set recording and simulation but also the creation of virtual sensors or filters (e.g gyroscope drift compensation, linear acceleration, altimeter), and (iii) a map-matching algorithm that provides a new location based on a given OpenStreetMap file description and the current user's trajectory.

- Participant: Thibaud Michel

- Contact: Nabil Layaïda

- Publications: On Mobile Augmented Reality Applications based on Geolocation - Attitude Estimation for Indoor Navigation and Augmented Reality with Smartphones

- URL: http://tyrex.inria.fr/projects/mrb.html

5.4. Benchmarks Attitude Smartphones

KEYWORDS: Experimentation - Motion analysis - Sensors - Performance analysis - Smartphone
SCIENTIFIC DESCRIPTION: We investigate the precision of attitude estimation algorithms in the particular context of pedestrian navigation with commodity smartphones and their inertial/magnetic sensors. We report on an extensive comparison and experimental analysis of existing algorithms. We focus on typical motions of smartphones when carried by pedestrians. We use a precise ground truth obtained from a motion capture system. We test state-of-the-art attitude estimation techniques with several smartphones, in the presence of magnetic perturbations typically found in buildings. We discuss the obtained results, analyze advantages and limits of current technologies for attitude estimation in this context. Furthermore, we propose a new technique for limiting the impact of magnetic perturbations with any attitude estimation algorithm used in this context. We show how our technique compares and improves over previous works.

- Participants: Hassen Fourati, Nabil Layaïda, Pierre Genevès and Thibaud Michel

- Partner: GIPSA-Lab

- Contact: Pierre Genevès

- URL: http://tyrex.inria.fr/mobile/benchmarks-attitude/

5.5. MedAnalytics

KEYWORDS: Big data - Predictive analytics - Distributed systems
FUNCTIONAL DESCRIPTION: We implemented a method for the automatic detection of at-risk profiles based on a fine-grained analysis of prescription data at the time of admission. The system relies on an optimized distributed architecture adapted for processing very large volumes of medical records and clinical data. We conducted practical experiments with real data of millions of patients and hundreds of hospitals. We demonstrated how the various perspectives of big data improve the detection of at-risk patients, making it possible to construct predictive models that benefit from volume and variety. This prototype implementation is described in the 2017 preprint available at: https://hal.inria.fr/hal-01517087/document.

- Participants: Pierre Genevès and Thomas Calmant

- Partner: CHU Grenoble

- Contact: Pierre Genevès

- Publication: Scalable Machine Learning for Predicting At-Risk Profiles Upon Hospital Admission

5.6. MuIR

Mu Intermediate Representation

KEYWORDS: Optimizing compiler - Querying

FUNCTIONAL DESCRIPTION: This is a prototype of an intermediate language representation, i.e. an implementation of algebraic terms, rewrite rules, query plans, cost model, query optimizer, and query evaluators (including a distributed evaluator of algebraic terms using Apache Spark).

- Contact: Pierre Genevès

VALDA Project-Team

5. New Software and Platforms

5.1. ProvSQL

KEYWORDS: Databases - Provenance - Probability
FUNCTIONAL DESCRIPTION: The goal of the ProvSQL project is to add support for (m-)semiring provenance and uncertainty management to PostgreSQL databases, in the form of a PostgreSQL extension/module/plugin.
NEWS OF THE YEAR: Support for where-provenance has been completed. Numerous bug fixes. A docker version has been produced, for ease of installation. Demonstration scenarios are included.

- Participants: Pierre Senellart and Yann Ramusat

- Contact: Pierre Senellart

- Publications: Provenance and Probabilities in Relational Databases: From Theory to Practice - ProvSQL: Provenance and Probability Management in PostgreSQL

- URL: https://github.com/PierreSenellart/provsql

5.2. WAE

Web archive explorer
KEYWORDS: Information extraction - Web archives
FUNCTIONAL DESCRIPTION: The Web archive explorer is a system for extracting, fragmenting and exploring Web archives.

- Contact: Quentin Lobbe

- Publications: Archives, Web fragments and diasporas. For a disaggregated exploration of web archives related to online representations of diasporas - Where the dead blogs are. A Disaggregated Exploration of Web Archives to Reveal Extinct Online Collectives - Revealing Historical Events out of Web Archives

- URL: https://github.com/lobbeque/archive-miner

5.3. apxproof

KEYWORD: LaTeX
FUNCTIONAL DESCRIPTION: apxproof is a LaTeX package facilitating the typesetting of research articles with proofs in appendix, a common practice in database theory and theoretical computer science in general. The appendix material is written in the LaTeX code along with the main text which it naturally complements, and it is automatically deferred. The package can automatically send proofs to the appendix, can repeat in the appendix the theorem environments stated in the main text, can section the appendix automatically based on the sectioning of the main text, and supports a separate bibliography for the appendix material.

RELEASE FUNCTIONAL DESCRIPTION: Numerous bug fixes and robustness enhancements, link theorems to their repeated Versions, proper management of equations in repeated theorems
NEWS OF THE YEAR: Major 1.1.0 release adding several features (link theorems to their repeated versions, proper management of equations in repeated theorems), beyond this, bug fixes, robustness enhancements, better support for some document classes.

- Participant: Pierre Senellart

- Contact: Pierre Senellart

- URL: https://github.com/PierreSenellart/apxproof

5.4. Sgvizler2

KEYWORDS: SPARQL - Data visualization - JavaScript
FUNCTIONAL DESCRIPTION: This project is the reboot in Typescript of project Sgvizler of Martin G. Skjæveland.

- Partners: LRI - Laboratoire de Recherche en Informatique - BorderCloud
- Contact: Karima Rafes
- URL: https://github.com/BorderCloud/sgvizler2

5.5. SPARQL-PHP

KEYWORDS: SPARQL - PHP
FUNCTIONAL DESCRIPTION: Very simple SPARQL client for PHP.

- Partners: LRI - Laboratoire de Recherche en Informatique - BorderCloud
- Contact: Karima Rafes
- URL: https://github.com/BorderCloud/SPARQL

5.6. TFT

Tester for Triplestore
KEYWORDS: PHP - SPARQL
FUNCTIONAL DESCRIPTION: TFT (Tester for Triplestore) is a script PHP to pass tests through a SPARQL service.

- Partners: LRI - Laboratoire de Recherche en Informatique - BorderCloud
- Contact: Karima Rafes
- URL: https://github.com/BorderCloud/TFT

<p align="center" style="color:red">WIMMICS Project-Team</p>

6. New Software and Platforms

6.1. CORESE

COnceptual REsource Search Engine
KEYWORDS: Semantic Web - Search Engine - RDF - SPARQL
FUNCTIONAL DESCRIPTION: Corese is a Semantic Web Factory, it implements W3C RDF, RDFS, SPARQL 1 .1 Query and Update as well as RDF Inference Rules.

Furthermore, Corese query language integrates original features such as approximate search and extended Property Path. It provides STTL: SPARQL Template Transformation Language for RDF graphs. It also provides LDScript: a Script Language for Linked Data. Corese provides distributed federated query processing.

- Participants: Erwan Demairy, Fabien Gandon, Fuqi Song, Olivier Corby, Olivier Savoie and Virginie Bottollier
- Partners: I3S - Mnemotix
- Contact: Olivier Corby
- URL: http://wimmics.inria.fr/corese

6.2. DBpedia

KEYWORDS: RDF - SPARQL
FUNCTIONAL DESCRIPTION: DBpedia is an international crowd-sourced community effort to extract structured information from Wikipedia and make this information available on the semantic Web as linked open data. The DBpedia triple stores then allow anyone to solve sophisticated queries against Wikipedia extracted data, and to link the different data sets on these data. The French chapter of DBpedia was created and deployed by Wimmics and is now an online running platform providing data to several projects such as: QAKIS, Izipedia, zone47, Sépage, HdA Lab., JocondeLab, etc.

RELEASE FUNCTIONAL DESCRIPTION: The new release is based on updated Wikipedia dumps and the inclusion of the DBpedia history extraction of the pages.

- Participants: Fabien Gandon and Elmahdi Korfed
- Contact: Fabien Gandon
- URL: http://wiki.dbpedia.org/

6.3. Discovery Hub

Discovery Hub Exploratory Search Engine
KEYWORD: Search Engine
FUNCTIONAL DESCRIPTION: Recommandation system on top of DBpedia

- Participants: Alain Giboin, Emilie Palagi, Fabien Gandon and Nicolas Marie
- Partner: Alcatel-Lucent
- Contact: Fabien Gandon
- URL: http://discoveryhub.co/

6.4. Fuzzy labelling argumentation module

Fuzzy labelling algorithm for abstract argumentation
KEYWORDS: Artificial intelligence - Multi-agent - Knowledge representation - Algorithm

FUNCTIONAL DESCRIPTION: The goal of the algorithm is to compute the fuzzy acceptability degree of a set of arguments in an abstract argumentation framework. The acceptability degree is computed from the trustworthiness associated with the sources of the arguments.

- Participant: Serena Villata Milanesio
- Contact: Serena Villata Milanesio

6.5. Qakis

Question-Answering wiki framework based system
KEYWORD: Natural language
FUNCTIONAL DESCRIPTION: The QAKiS system implements question answering over DBpedia. QAKiS allows end users to submit a query to an RDF triple store in English and to obtain the answer in the same language, hiding the complexity of the non-intuitive formal query languages involved in the resolution process. At the same time, the expressiveness of these standards is exploited to scale to the huge amounts of available semantic data. Its major novelty is to implement a relation-based match for question interpretation, to convert the user question into a query language (e.g. SPARQL). English, French and German DBpedia chapters are the RDF data sets to be queried using a natural language interface.

- Participants: Alessio Palmero Aprosio, Amine Hallili, Elena Cabrio, Fabien Gandon, Julien Cojan and Serena Villata Milanesio
- Contact: Elena Cabrio
- URL: http://www.qakis.org/

<p align="center" style="color:red">**ZENITH Project-Team**</p>

6. New Software and Platforms

6.1. Pl@ntNet

KEYWORDS: Plant identification - Deep learning - Citizen science

FUNCTIONAL DESCRIPTION: Pl@ntNet is a participatory platform and information system dedicated to the production of botanical data through deep learning-based plant identification. It includes 3 main front-ends, an Android app (the most advanced and the most used one), an iOs app (being currently re-developed) and a web version. The main feature of the application is to return the ranked list of the most likely species providing an image or an image set of an individual plant. In addition, Pl@ntNet's search engine returns the images of the dataset that are the most similar to the queried observation allowing interactive validation by the users. The back-office running on the server side of the platform is based on Snoop visual search engine (a software developed by ZENITH) and on NewSQL technologies for the data management. The application is distributed in more than 180 countries (10M downloads) and allows identifying about 20K plant species at present time.

- Participants: Antoine Affouard, Jean-Christophe Lombardo, Pierre Bonnet, Hervé Goëau, Mathias Chouet and Julien Champ
- Contact: Alexis Joly
- Publication: Pl@ntNet app in the era of deep learning

6.2. ThePlantGame

KEYWORD: Crowd-sourcing

FUNCTIONAL DESCRIPTION: ThePlantGame is a participatory game whose purpose is the production of big taxonomic data to improve our knowledge of biodiversity. One major contribution is the active training of the users based on innovative sub-task creation and assignment processes that are adaptive to the increasing skills of the user. Thousands of players are registered and produce on average about tens new validated plant observations per day. The accuracy of the produced taxonnomic tags is very high (about 95

- Participants: Maximilien Servajean and Alexis Joly
- Contact: Alexis Joly
- Publication: Crowdsourcing Thousands of Specialized Labels: A Bayesian Active Training Approach

6.3. Snoop

KEYWORDS: Content-based Image Retrieval - Deep learning

FUNCTIONAL DESCRIPTION: Snoop is a C++ framework dedicated to large-scale content-based image retrieval. Its main features are (i) the extraction and efficient indexing of visual features (hand-crafted or learned through deep learning), (ii) the search of similar images through approximate k-nearest neighbors and (iii), the supervised recognition of trained visual concepts. The framework can be used either as a set of C++ libraries or as a set of web services through a RESTFUL API. Snoop is the visual search engine used by the Pl@ntNet applications (very large audience).

- Participants: Alexis Joly, Jean-Christophe Lombardo and Olivier Buisson
- Partner: INA (Institut National de l'Audiovisuel)
- Contact: Alexis Joly
- Publication: Random Maximum Margin Hashing

6.4. Chiaroscuro

KEYWORDS: Privacy - P2P - Data mining

FUNCTIONAL DESCRIPTION: Chiaroscuro is a complete solution for clustering personal data with strong privacy guarantees. The execution sequence produced by Chiaroscuro is massively distributed on personal devices, coping with arbitrary connections and disconnections. Chiaroscuro builds on our novel data structure, called Diptych, which allows the participating devices to collaborate privately by combining encryption with differential privacy. Our solution yields a high clustering quality while minimizing the impact of the differentially private perturbation.

- Participants: Tristan Allard, Georges Hebrail, Florent Masseglia and Esther Pacitti
- Contact: Florent Masseglia
- Publication: Chiaroscuro: Transparency and Privacy for Massive Personal Time-Series Clustering

6.5. DfAnalyzer

Dataflow Analysis

KEYWORDS: Data management - Monitoring - Runtime Analysis

FUNCTIONAL DESCRIPTION: DfAnalyzer is a tool for monitoring, debugging, steering, and analysis of dataflows while being generated by scientific applications. It works by capturing strategic domain data, registering provenance and execution data to enable queries at runtime. DfAnalyzer provides lightweight dataflow monitoring components to be invoked by high performance applications. It can be plugged in scripts, or Spark applications, in the same way users already plug visualization library components.

- Participants: Vítor Sousa Silva, Daniel De Oliveira, Marta Mattoso and Patrick Valduriez
- Partners: COPPE/UFRJ - Uff
- Contact: Patrick Valduriez
- Publication: DfAnalyzer: Runtime Dataflow Analysis of Scientific Applications using Provenance
- URL: https://github.com/vssousa/dfanalyzer-spark

6.6. CloudMdsQL Compiler

KEYWORDS: Optimizing compiler - NoSQL - Data integration

FUNCTIONAL DESCRIPTION: The CloudMdsQL (Cloud Multi-datastore Query Language) polystore transforms queries expressed in a common SQL-like query language into an optimized query execution plan to be executed over multiple cloud data stores (SQL, NoSQL, HDFS, etc.) through a query engine. The compiler/optimizer is implemented in C++ and uses the Boost.Spirit framework for parsing context-free grammars. CloudMdsQL has been validated on relational, document and graph data stores in the context of the CoherentPaaS European project.

- Participants: Boyan Kolev, Oleksandra Levchenko and Patrick Valduriez
- Contact: Patrick Valduriez
- Publication: CloudMdsQL: Querying Heterogeneous Cloud Data Stores with a Common Language

6.7. Savime

Simulation And Visualization IN-Memory

KEYWORDS: Data management. - Distributed Data Management

FUNCTIONAL DESCRIPTION: SAVIME is a multi-dimensional array DBMS for scientific applications. It supports a novel data model called TARS (Typed ARray Schema), which extends the basic array data model with typed arrays. In TARS, the support of application dependent data characteristics is provided through the definition of TAR objects, ready to be manipulated by TAR operators. This approach provides much flexibility for capturing internal data layouts through mapping functions, which makes data ingestion independent of how simulation data has been produced, thus minimizing ingestion time.

- Participants: Hermano Lustosa, Fabio Porto and Patrick Valduriez
- Partner: LNCC - Laboratório Nacional de Computação Científica
- Contact: Patrick Valduriez
- Publication: TARS: An Array Model with Rich Semantics for Multidimensional Data

6.8. OpenAlea

KEYWORDS: Bioinformatics - Biology

FUNCTIONAL DESCRIPTION: OpenAlea is an open source project primarily aimed at the plant research community. It is a distributed collaborative effort to develop Python libraries and tools that address the needs of current and future works in Plant Architecture modeling. It includes modules to analyze, visualize and model the functioning and growth of plant architecture. It was formally developed in the Inria VirtualPlants team.

RELEASE FUNCTIONAL DESCRIPTION: OpenAlea 2.0 adds to OpenAlea 1.0 a high-level formalism dedicated to the modeling of morphogenesis that makes it possible to use several modeling paradigms (Blackboard, L-systems, Agents, Branching processes, Cellular Automata) expressed with different languages (Python, L-Py, R, Visual Porgramming, ...) to analyse and simulate shapes and their development.

- Participants: Christian Fournier, Christophe Godin, Christophe Pradal, Frédéric Boudon, Patrick Valduriez, Esther Pacitti and Yann Guedon
- Partners: CIRAD - INRA
- Contact: Christophe Pradal
- Publications: OpenAlea: Scientific Workflows Combining Data Analysis and Simulation - OpenAlea: A visual programming and component-based software platform for plant modeling

6.9. FP-Hadoop

Fast Parallel Hadoop

KEYWORDS: Hadoop - Data parallelism

FUNCTIONAL DESCRIPTION: FP-Hadoop makes the reduce side of Hadoop MapReduce more parallel and efficiently deals with the problem of data skew in the reduce side. In FP-Hadoop, there is a new phase, called intermediate reduce (IR), in which blocks of intermediate values, constructed dynamically, are processed by intermediate reduce workers in parallel. Our experiments using FP-Hadoop using synthetic and real benchmarks have shown excellent performance gains compared to native Hadoop, e.g. more than 10 times in reduce time and 5 times in total execution time.

- Participants: Reza Akbarinia, Miguel Liroz-Gistau and Patrick Valduriez
- Contact: Reza Akbarinia
- Publication: FP-Hadoop: Efficient Execution of Parallel Jobs Over Skewed Data

6.10. Hadoop_g5k

KEYWORD: Cluster

FUNCTIONAL DESCRIPTION: Hadoop_g5k is a tool that makes it easier to manage Hadoop and Spark clusters and prepare reproducible experiments in the Grid 5000 platform. Hadoop_g5k offers a set of scripts to be used in command-line interfaces and a Python API to interact with the clusters. It is currently active within the G5k community, facilitating the preparation and execution of experiments in the platform.

- Participants: Reza Akbarinia, Miguel Liroz-Gistau and Patrick Valduriez
- Contact: Reza Akbarinia
- URL: https://www.grid5000.fr/mediawiki/index.php/Hadoop_On_Execo

6.11. Triton Server

End-to-end Graph Mapper
KEYWORD: Web Application
FUNCTIONAL DESCRIPTION: A server for managing graph data and applications for mobile social networks. The server is built on top of the OrientDB graph database system and a distributed middleware. It provides an End-to-end Graph Mapper (EGM) for modeling the whole application as (i) a set of graphs representing the business data, the in-memory data structure maintained by the application and the user interface (tree of graphical components), and (ii) a set of standardized mapping operators that maps these graphs with each other.

- Participants: Didier Parigot, Patrick Valduriez and Benjamin Billet
- Contact: Didier Parigot
- Publication: End-to-end Graph Mapper

6.12. SON

Shared-data Overlay Network
KEYWORDS: Sharing - Ibuted exchange - Peer-to-peer.
FUNCTIONAL DESCRIPTION: SON is a development platform for P2P networks using web services, JXTA and OSGi. The development of a SON application is done through the design and implementation of a set of components. Each component includes a technical code that provides the component services and a code component that provides the component logic (in Java). The complex aspects of asynchronous distributed programming are separated from code components and automatically generated from an abstract description of services for each component by the component generator.

- Participants: Didier Parigot, Esther Pacitti and Patrick Valduriez
- Contact: Didier Parigot
- Publication: A Lightweight Middleware for developing P2P Applications with Component and Service-Based Principles
- URL: http://www-sop.inria.fr/members/Didier.Parigot/pmwiki/SON/index.php

6.13. SciFloware

Scientific Workflow Middleware
KEYWORDS: Bioinformatics - Distributed Data Management
FUNCTIONAL DESCRIPTION: SciFloware is a middleware for the execution of scientific workflows in a distributed and parallel way. It capitalizes on our experience with the Shared-Data Overlay Network and an innovative algebraic approach to the management of scientific workflows. SciFloware provides a development environment and a runtime environment for scientific workflows, interoperable with existing systems. We validate SciFloware with workflows for analyzing biological data provided by our partners CIRAD, INRA and IRD.

- Participants: Didier Parigot, Dimitri Dupuis and Patrick Valduriez
- Contact: Didier Parigot
- Publication: InfraPhenoGrid: A scientific workflow infrastructure for Plant Phenomics on the Grid
- URL: http://www-sop.inria.fr/members/Didier.Parigot/pmwiki/Scifloware

6.14. WebSmatch

Web Schema Matching

KEYWORD: Data integration

FUNCTIONAL DESCRIPTION: WebSmatch is a flexible, open environment for discovering and matching complex schemas from heterogeneous Web data sources. It provides three basic functions: (1) metadata extraction from data sources, (2) schema matching, (3) schema clustering to group similar schemas together. WebSmatch is delivered through Web services, to be used directly by data integrators or other tools with RIA clients. It is implemented in Java, delivered as Open Source Software (under LGPL). WebSmatch has been used by Data Publica and CIRAD to integrate public and private data sources.

- Participants: Emmanuel Castanier, Patrick Valduriez and Rémi Coletta
- Contact: Patrick Valduriez
- Publication: WebSmatch: a tool for Open Data
- URL: http://websmatch.gforge.inria.fr/

<h1 align="center" style="color:red">ALICE Project-Team</h1>

6. New Software and Platforms

6.1. Graphite

Graphite: The Numerical Geometry Workbench

KEYWORDS: 3D modeling - Numerical Geometry - Texturing - Lighting - CAD - Visualization

SCIENTIFIC DESCRIPTION: Graphite is an experimental 3D modeler, built on top of the Geogram programming library. It has data structures and efficient OpenGL visualization for pointsets, surfacic meshes (triangles and polygons), volumetric meshes (tetrahedra and hybrid meshes). It has state-of-the-art mesh repair, remeshing, reconstruction algorithms. It also has an interface to the Tetgen tetrahedral mesh generator (by Hang Si). This year, Graphite3 was released. It is a major rewrite, based on Geogram, with increased software quality standards (zero warnings on all platforms, systematic documentation of all classes / all functions / all parameters, dramatically improved performances). It embeds Geogram (and optionally Vorpaline) with an easy-to-use Graphic User Interface.

FUNCTIONAL DESCRIPTION: Graphite is a dedicated software platform in numerical geometry that enables, among other things, 3D modelling and texture baking.

- Participants: Bruno Lévy, David Lopez, Dobrina Boltcheva, Jeanne Pellerin, Nicolas Ray and Samuel Hornus
- Contact: Bruno Lévy
- URL: http://alice.loria.fr/software/graphite

6.2. GEOGRAM

GEOGRAM : A functions library for geometric programming

KEYWORD: 3D modeling

FUNCTIONAL DESCRIPTION: GEOGRAM is a programming library with a set of basic geometric algorithms, such as search data structures (AABB tree, Kd tree), geometric predicates, triangulations (Delaunay triangulation, Regular triangulation), intersection between a simplicial mesh and a Voronoi diagram (restricted Voronoi diagram). GEOGRAM also includes a code generator for predicates (PCK: Predicate Construction Kit) and an efficient implementation of expansion arithmetics in arbitrary precision. GEOGRAM is shipped with WARP-DRIVE, the first program that computes semi-discrete optimal transport in 3D.

- Participant: Bruno Lévy
- Contact: Bruno Lévy
- URL: http://alice.loria.fr

6.3. OpenNL

Open Numerical Library

KEYWORDS: 3D modeling - Numerical algorithm

FUNCTIONAL DESCRIPTION: Open Numerical Library is a library for solving sparse linear systems, especially designed for the Computer Graphics community. The goal for OpenNL is to be as small as possible, while offering the subset of functionalities required by this application field. The Makefiles of OpenNL can generate a single .c + .h file, very easy to integrate in other projects. The distribution includes an implementation of the Least Squares Conformal Maps parameterization method.

RELEASE FUNCTIONAL DESCRIPTION: Latest version available as part of GEOGRAM:

∗ OpenMP parallel solver

∗ more compact data structures, X2 acceleration

∗ SuperLU weak coupling (dynamically loads SuperLU .so if available)

- Participants: Bruno Lévy, Nicolas Ray and Rhaleb Zayer
- Contact: Bruno Lévy
- URL: http://alice.loria.fr/index.php/software/4-library/23-opennl.html

6.4. IceSL

KEYWORD: Additive manufacturing
FUNCTIONAL DESCRIPTION: IceSL allows to model complex shapes through CSG boolean operations. Objects can be directly prepared and sent to a 3d printer for fabrication, without the need to compute an intermediate 3D mesh.

- Participants: Frédéric Claux, Jean Hergel, Jérémie Dumas, Jonas Martinez-Bayona, Samuel Hornus and Sylvain Lefebvre
- Contact: Sylvain Lefebvre
- URL: http://shapeforge.loria.fr/icesl/

6.5. LibSL

Simple Library For Graphics
KEYWORDS: 3D - Graphics
FUNCTIONAL DESCRIPTION: LibSL is a toolbox for rapid prototyping of computer graphics algorithms, under both OpenGL, DirectX 9 - 10, Windows and Linux.

- Participant: Sylvain Lefebvre
- Contact: Sylvain Lefebvre

6.6. 3DPrintScaffoldings

KEYWORDS: 3D - 3D modeling - Additive manufacturing
FUNCTIONAL DESCRIPTION: Support generation for additive manufacturing. Optimizes scaffolding made of vertical pillars and horizontal bars that are optimized to use minimal material, be easily removed and support the part at all stages of the fabrication process.

- Participants: Jean Hergel, Jérémie Dumas and Sylvain Lefebvre
- Partner: Université de Lorraine
- Contact: Sylvain Lefebvre
- URL: http://shapeforge.loria.fr/icesl/

6.7. VORPALINE

VORPALINE mesh generator
KEYWORDS: 3D modeling - Unstructured heterogeneous meshes
FUNCTIONAL DESCRIPTION: VORPALINE is a surfacic and volumetric mesh generator, for simplicial meshes (triangles and tetrahedra), for quad-dominant and hex-dominant meshes.

- Participant: Bruno Lévy
- Contact: Bruno Lévy
- URL: http://alice.loria.fr/index.php/erc-vorpaline.html

<p style="text-align:center">**AVIZ Project-Team**</p>

5. New Software and Platforms

5.1. Cartolabe

KEYWORD: Information visualization

FUNCTIONAL DESCRIPTION: The goal of Cartolabe is to build a visual map representing the scientific activity of an institution/university/domain from published articles and reports. Using the HAL Database and building upon the AnHALytics processing chain, Cartolabe provides the user with a map of the thematics, authors and articles and their dynamics along time. ML techniques are used for dimensionality reduction, cluster and topics identification, visualisation techniques are used for a scalable 2D representation of the results.

NEWS OF THE YEAR: Improvement of the graphical interface

- Contact: Philippe Caillou
- URL: http://cartolabe.lri.fr/

5.2. BitConduite

BitConduite Bitcoin explorer

KEYWORDS: Data visualization - Clustering - Financial analysis - Cryptocurrency

FUNCTIONAL DESCRIPTION: BitConduite is a web-based visual tool that allows for a high level explorative analysis of the Bitcoin blockchain. It offers a data transformation back end that gives us an entity-based access to the blockchain data and a visualization front end that supports a novel high-level view on transactions over time. In particular, it facilitates the exploration of activity through filtering and clustering interactions. This gives analysts a new perspective on the data stored on the blockchain.

- Contact: Petra Isenberg

EX-SITU Project-Team

6. New Software and Platforms

6.1. Platforms

6.1.1. WildOS

Participant: Michel Beaudouin-Lafon [correspondant].

WildOS is middleware designed to support applications that run in an interactive room, such as our WILD and WILDER rooms, with various interaction resources, including a tiled wall display, a motion tracking system, interactive tabletops, tablets, smartphones and custom-made or 3d printed interactive devices. The conceptual model of WildOS is a *platform*, such as the WILD or WILDER room, that can be described as a set of devices on which one or more applications can be run.

WildOS consists of a server running on a machine that has network access to all the machines involved in the platform, and a set of clients running on the various interaction resources, such as a display cluster or a tablet. Once *WildOS* is running, applications can be started and stopped and devices can be added to or removed from the platform.

WildOS relies on Web technologies, most notably Javascript and node.js, as well as node-webkit and HTML5. This makes it inherently portable (it is currently tested on Mac OS X and Linux). While applications can be developed only with these Web technologies, it is also possible to bridge to existing applications developed in other environments if they provide sufficient access for remote control. Sample applications include a web browser, an image viewer, a window manager, and the BrainTwister application developed in collaboration with neuroanatomists at NeuroSpin.

WildOS is used for several research projects at ExSitu and by other partners of the Digiscope project. It was also deployed on several of Google's interactive rooms in Mountain View, Dublin and Paris. It is available under on Open Source licence at https://bitbucket.org/mblinsitu/wildos.

- ACM: H.5.2 [User Interfaces]: Graphical user interfaces (GUI)
- Software benefit: helps development of multisurface applications.
- OS/Middleware: Crossplatform
- Required library or software: node.js, node-webkit
- Programming language: Javascript

6.1.2. Unity Cluster

Participants: Cédric Fleury [correspondant], Olivier Gladin [SED-SAC].

Unity Cluster is middleware to distribute any Unity 3D (https://unity3d.com/) application on a cluster of computers that run in interactive rooms, such as our WILD and WILDER rooms, or immersive CAVES (Computer-Augmented Virtual Environments). Users can interact the the application with various interaction resources.

Unity Cluster provides an easy solution for running existing Unity 3D applications on any display that requires a rendering cluster with several computers. *Unity Cluster* is based on a master-slave architecture: The master computer runs the main application and the physical simulation as well as manages the input; the slave computers receive updates from the master and render small parts of the 3D scene. *Unity Cluster* manages data distribution and synchronization among the computers to obtain a consistent image on the entire wall-sized display surface.

Unity Cluster can also deform the displayed images according to the user's position in order to match the viewing frustum defined by the user's head and the four corners of the screens. This respects the motion parallax of the 3D scene, giving users a better sense of depth.

Unity Cluster is composed of a set of C Sharp scripts that manage the network connection, data distribution, and the deformation of the viewing frustum. In order to distribute an existing application on the rendering cluster, all scripts must be embedded into a Unity package that is included in an existing Unity project.

- ACM: C.2.4 [Distributed Systems]: Distributed applications, I.3.7 [3D Graphics and Realism]: Virtual reality

- Software benefit: adapts existing Unity 3D application to a rendering cluster of an interactive room.

- OS/Middleware: Crossplatform

- Required library or software: Unity 3D

- Programming language: C Sharp

6.1.3. WILDER

Participants: Michel Beaudouin-Lafon [correspondant], Cédric Fleury, Olivier Gladin.

WILDER (Figure 1) is our second experimental ultra-high-resolution interactive environment, which follows the WILD platform developed in 2009. It features a wall-sized display with seventy-five 20" LCD screens, i.e. a 5m50 x 1m80 (18' x 6') wall displaying 14 400 x 4 800 = 69 million pixels, powered by a 10-computer cluster and two front-end computers. The platform also features a camera-based motion tracking system that lets users interact with the wall, as well as the surrounding space, with various mobile devices. The display uses a multitouch frame (the largest of its kind in the world) to make the entire wall touch sensitive.

WILDER was inaugurated in June, 2015. It is one of the ten platforms of the Digiscope Equipment of Excellence and, in combination with WILD and the other Digiscope rooms, provides a unique experimental environment for collaborative interaction.

In addition to using WILD and WILDER for our research, we have also developed software architectures and toolkits, such as WildOS and Unity Cluster, that enable developers to run applications on these multi-device, cluster-based systems.
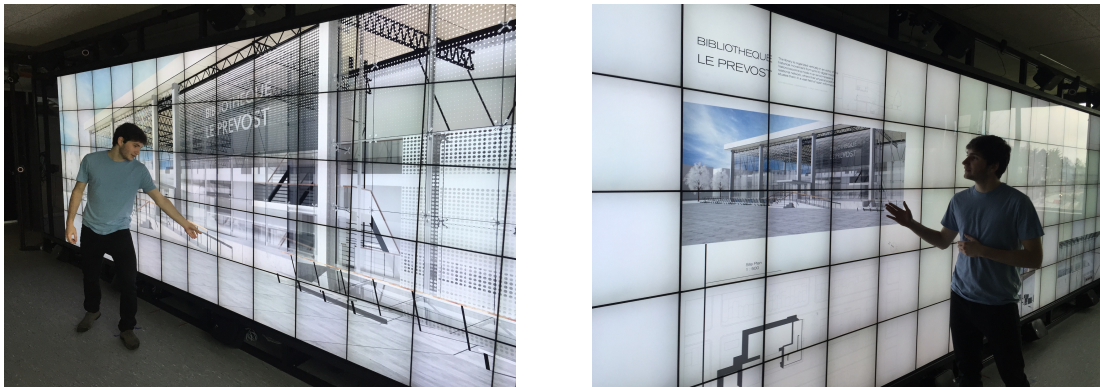

Figure 1. The WILDER platform.

GRAPHDECO Project-Team

5. New Software and Platforms

5.1. SGTDGP

Synthetic Ground Truth Data Generation Platform
KEYWORD: Graphics
FUNCTIONAL DESCRIPTION: The goal of this platform is to render large numbers of realistic synthetic images for use as ground truth to compare and validate image-based rendering algorithms and also to train deep neural networks developed in our team.

This pipeline consists of tree major elements that are:

- Scene exporter

- Assisted point of view generation

- Distributed rendering on Inria's high performance computing cluster

The scene exporter is able to export scenes created in the widely-used commercial modeler 3DSMAX to the Mitsuba opensource renderer format. It handles the conversion of complex materials and shade trees from 3DSMAX including materials made for VRay. The overall quality of the produced images with exported scenes have been improved thanks to a more accurate material conversion. The initial version of the exporter was extended and improved to provide better stability and to avoid any manual intervention.

From each scene we can generate a large number of images by placing multiple cameras. Most of the time those points of view has to be placed with a certain coherency. This task could be long and tedious. In the context of image-based rendering, cameras have to be placed in a row with a specific spacing. To simplify this process we have developed a set of tools to assist the placement of hundreds of cameras along a path.

The rendering is made with the open source renderer Mitsuba. The rendering pipeline is optimised to render a large number of point of view for single scene. We use a path tracing algorithm to simulate the light interaction in the scene and produce hight dynamic range images. It produces realistic images but it is computationally demanding. To speed up the process we setup an architecture that takes advantage of the Inria cluster to distribute the rendering on hundreds of CPUs cores.

The scene data (geometry, textures, materials) and the cameras are automatically transfered to remote workers and HDR images are returned to the user.

We already use this pipeline to export tens of scenes and to generate several thousands of images, which have been used for machine learning and for ground-truth image production.

We have recently integrated the platform with the SIBR software library, allowing us to read mitsuba scenes. We have written a tool to allow camera placement to be used for rendering and for reconstruction of synthetic scenes, including alignment of the exact and reconstructed version of the scenes. This dual-representation scenes can be used for learning and as ground truth. We can also perform various operations on the ground truth data within SIBR, e.g., compute shadow maps of both exact and reconstructed representations etc.

- Contact: George Drettakis

5.2. Unity IBR

KEYWORD: Graphics

FUNCTIONAL DESCRIPTION: Unity IBR (for Image-Based Rendering in Unity) This is a software module that proceeds the development of IBR algorithms in Unity. In this case, algorithms are developed for the context of EMOTIVE EU project. The rendering technique was changed during the year to evaluate and compare which one produces better results suitable for Game Development with Unity (improvement of image quality and faster rendering). New features were also added such as rendering of bigger datasets and some debugging utilities. Software was also updated to keep compatibility with new released versions of Unity game engine. In addition, in order to develop a demo showcasing the technology, a multiplayer VR scene was created proving the integration of IBR with the rest of the engine.

- Contact: George Drettakis

5.3. SIBR

Simple Image-Based Rendering
KEYWORD: Graphics
FUNCTIONAL DESCRIPTION: This is a framework containing libraries and tools used internally for research projects based on Image-Base Rendering. It includes both preprocessing tools (computing data used for rendering) and rendering utilities and serves as the basis for many research projects in the group.

It includes basic support for a large set of computer graphics and computer vision functionalities and includes implementations of several image-based rendering algorithms. The code base has become quite mature and is in the process of being used for tech transfer.

- Contact: George Drettakis

5.4. SynthDraw

KEYWORDS: Non-photorealistic rendering - Vector-based drawing
FUNCTIONAL DESCRIPTION: The SynthDraw library extracts occluding contours and sharp features over a 3D shape, computes all their intersections using a binary space partitionning algorithm, and finally makes a raycast to determine each sub-contour visibility. The resulting lines can then be exported as an SVG file for subsequent processing, for instance to stylize the drawing with different brush strokes. The library can also export various attributes for each line, such as its visibility and type. SynthDraw is based on the geometry processing library libIGL.

RELEASE FUNCTIONAL DESCRIPTION: This first version extracts occluding contours and creases, and computes their visibility with brute-force ray casting.

- Contact: Bastien Wailly

5.5. DeepSketch

KEYWORDS: 3D modeling - Sketching - Deep learning
FUNCTIONAL DESCRIPTION: DeepSketch is a sketch-based modeling system that runs in a web browser. It relies on deep learning to recognize geometric shapes in line drawings. The system follows a client/server architecture, based on the Node.js and WebGL technology. The application's main targets are iPads or Android tablets equipped with a digital pen, but it can also be used on desktop computers.

RELEASE FUNCTIONAL DESCRIPTION: This first version is built around a client/server Node.js application whose job is to transmit a drawing from the client's interface to the server where the deep networks are deployed, then transmit the results back to the client where the final shape is created and rendered in a WebGL 3D scene thanks to the THREE.js JavaScript framework. Moreover, the client is able to perform various camera transformations before drawing an object (change position, rotate in place, scale on place) by interacting with the touch screen. The user also has the ability to draw the shape's shadow to disambiguate depth/height. The deep networks are created, trained and deployed with the Caffe framework.

- Contact: Adrien Bousseau

HYBRID Project-Team

6. New Software and Platforms

6.1. #FIVE

Framework for Interactive Virtual Environments

KEYWORDS: Virtual reality - 3D - 3D interaction - Behavior modeling

SCIENTIFIC DESCRIPTION: #FIVE (Framework for Interactive Virtual Environments) is a framework for the development of interactive and collaborative virtual environments. #FIVE was developed to answer the need for an easier and a faster design and development of virtual reality applications. #FIVE provides a toolkit that simplifies the declaration of possible actions and behaviours of objects in a VE. It also provides a toolkit that facilitates the setting and the management of collaborative interactions in a VE. It is compliant with a distribution of the VE on different setups. It also proposes guidelines to efficiently create a collaborative and interactive VE. The current implementation is in C# and comes with a Unity3D engine integration, compatible with MiddleVR framework.

FUNCTIONAL DESCRIPTION: #FIVE contains software modules that can be interconnected and helps in building interactive and collaborative virtual environments. The user can focus on domain-specific aspects for his/her application (industrial training, medical training, etc) thanks to #FIVE's modules. These modules can be used in a vast range of domains using virtual reality applications and requiring interactive environments and collaboration, such as in training for example.

- Participants: Florian Nouviale, Valérie Gouranton, Bruno Arnaldi, Vincent Goupil, Carl-Johan Jorgensen, Emeric Goga, Adrien Reuzeau and Alexandre Audinot
- Contact: Valérie Gouranton
- Publication: #FIVE : High-Level Components for Developing Collaborative and Interactive Virtual Environments
- URL: https://bil.inria.fr/fr/software/view/2527/tab

6.2. #SEVEN

Sensor Effector Based Scenarios Model for Driving Collaborative Virtual Environments

KEYWORDS: Virtual reality - Interactive Scenarios - 3D interaction

SCIENTIFIC DESCRIPTION: #SEVEN (Sensor Effector Based Scenarios Model for Driving Collaborative Virtual Environments) is a model and an engine based on petri nets extended with sensors and effectors, enabling the description and execution of complex and interactive scenarios

FUNCTIONAL DESCRIPTION: #SEVEN enables the execution of complex scenarios for driving Virtual Reality applications. #SEVEN's scenarios are based on an enhanced Petri net model which is able to describe and solve intricate event sequences. #SEVEN comes with an editor for creating, editing and remotely controlling and running scenarios. #SEVEN is implemented in C# and can be used as a stand-alone application or as a library. An integration to the Unity3D engine, compatible with MiddleVR, also exists.

- Participants: Florian Nouviale, Valérie Gouranton, Bruno Arnaldi, Vincent Goupil, Emeric Goga, Carl-Johan Jorgensen, Adrien Reuzeau and Alexandre Audinot
- Contact: Valérie Gouranton
- Publications: Versatile Scenario Guidance for Collaborative Virtual Environments - Roles in Collaborative Virtual Environments for Training - Actions sequencing incollaborative virtual environment - Short Paper: #SEVEN, a Sensor Effector Based Scenarios Model for Driving Collaborative Virtual Environment
- URL: https://bil.inria.fr/fr/software/view/2528/tab

6.3. OpenVIBE

KEYWORDS: Neurosciences - Interaction - Virtual reality - Health - Real time - Neurofeedback - Brain-Computer Interface - EEG - 3D interaction

FUNCTIONAL DESCRIPTION: OpenViBE is a free and open-source software platform devoted to the design, test and use of Brain-Computer Interfaces (BCI). The platform consists of a set of software modules that can be integrated easily and efficiently to design BCI applications. The key features of OpenViBE software are its modularity, its high-performance, its portability, its multiple-users facilities and its connection with high-end/VR displays. The designer of the platform enables to build complete scenarios based on existing software modules using a dedicated graphical language and a simple Graphical User Interface (GUI). This software is available on the Inria Forge under the terms of the AGPL licence, and it was officially released in June 2009. Since then, the OpenViBE software has already been downloaded more than 60000 times, and it is used by numerous laboratories, projects, or individuals worldwide. More information, downloads, tutorials, videos, documentations are available on the OpenViBE website.

- Participants: Cédric Riou, Thierry Gaugry, Anatole Lécuyer, Fabien Lotte, Jussi Tapio Lindgren, Laurent Bougrain, Maureen Clerc and Théodore Papadopoulo
- Partners: INSERM - GIPSA-Lab
- Contact: Anatole Lécuyer
- URL: http://openvibe.inria.fr

6.4. Platforms

6.4.1. Platform: Immerstar

- Participants: Florian Nouviale, Ronan Gaugne
- URL: http://www.irisa.fr/immersia/

With the two virtual reality technological platforms Immersia and Immermove, grouped under the name Immerstar, the team has access to high-level scientific facilities. This equipment benefits the research teams of the center and has allowed them to extend their local, national and international collaborations. The Immerstar platform was granted by an Inria funding for the 2015-2019 period which enables several important evolutions. In particular, in 2018, an haptic system covering the entire volume of the Immersia platform has been installed, allowing various configurations from single haptic device usage to dual haptic devices usage with either one or two users. In addition, a motion platform designed to introduce motion feedback in powered wheelchair simulations has also been incorporated (see Figure 2).
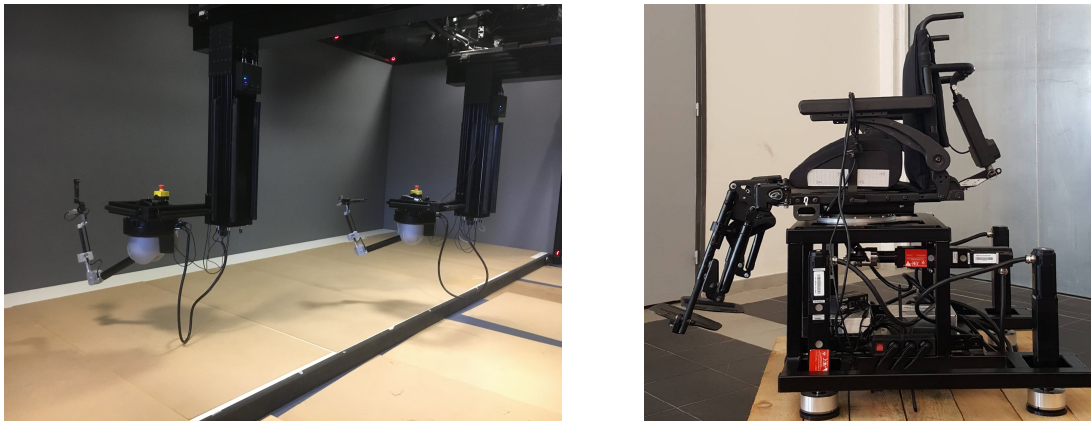
Figure 2. Upgrade of the Immersia platform: two new devices installed. (Left) "Scale-One" Haptic system for one or two users. (Right) Motion platform for powered wheelchair simulation.

ILDA Project-Team

5. New Software and Platforms

5.1. Smarties

FUNCTIONAL DESCRIPTION: The Smarties system provides an easy way to add mobile interactive support to collaborative applications for wall displays.

It consists of (i) a mobile interface that runs on mobile devices for input, (ii) a communication protocol between the mobiles and the wall application, and (iii) libraries that implement the protocol and handle synchronization, locking and input conflicts. The library presents the input as an event loop with callback functions and handles all communication between mobiles and wall application. Developpers can customize the mobile interface from the wall application without modifying the mobile interface code.

On each mobile we find a set of cursor controllers associated with keyboards, widgets and clipboards. These controllers (pucks) can be shared by multiple collaborating users. They can control simple cursors on the wall application, or specific content (objects or groups of them). The developer can decide the types of widgets associated to pucks from the wall application side.

- Contact: Olivier Chapuis
- URL: http://smarties.lri.fr/

5.2. ZVTM

Zoomable Visual Transformation Machine
KEYWORDS: Big data - Visualization - Data visualization - Information visualization - Graph visualization
FUNCTIONAL DESCRIPTION: ZVTM is a toolkit enabling the implementation of multi-scale interfaces for interactively navigating in large datasets displayed as 2D graphics.

ZVTM is used for browsing large databases in multiple domains: geographical information systems, control rooms of complex facilitites, astronomy, power distribution systems.

The toolkit also enables the development of applications running on ultra-high-resolution wall-sized displays.

- Participants: Caroline Appert, Olivier Chapuis and Emmanuel Pietriga
- Contact: Emmanuel Pietriga
- Publications: Rapid Development of User Interfaces on Cluster-Driven Wall Displays with jBricks - A Toolkit for Addressing HCI Issues in Visual Language Environments
- URL: http://zvtm.sf.net

5.3. MapMosaic

KEYWORDS: Geo-visualization - Data visualization
SCIENTIFIC DESCRIPTION: GIS software applications and other mapping tools enable users to correlate data from multiple layers and gain insight from the resulting visualizations. However, most of these applications only feature basic, monolithic layer compositing techniques. These techniques do not always support users effectively in their tasks, as we observed during interviews with GIS experts. MapMosaic is a novel approach based on dynamic visual compositing that enables users to interactively create and manipulate local composites of multiple vector and raster map layers, taking into account the semantics and attribute values of objects and fields in the composit-ing process. We evaluated MapMosaic's interaction model against that of QGIS (a widely-used desktop GIS) and MAPublisher (a professional cartography tool) using the "Cognitive Dimensions" framework and through an analytical comparison, showing that MapMosaic's model is more flexible and can support users more effectively in their tasks.

FUNCTIONAL DESCRIPTION: MapMosaic is a novel approach to combine geographical layers based on dynamic visual compositing that enables users to interactively create and manipulate local composites of multiple vector and raster map layers. It takes into account the semantics and attribute values of objects and fields in the compositing process. MapMosaic aims at better supporting GIS users in their tasks such as correlating data from multiple layers and gaining insight from the resulting visualizations.

RELEASE FUNCTIONAL DESCRIPTION: First public release.

- Participants: Maria Jesus Lobo Gunther, Caroline Appert and Emmanuel Pietriga
- Contact: Emmanuel Pietriga
- Publications: MapMosaic: Dynamic Layer Compositing for Interactive Geovisualization - An Evaluation of Interactive Map Comparison Techniques
- URL: http://ilda.saclay.inria.fr/mapmuxing/mapmosaic/index.html

5.4. Baia

Before-and-after satellite image animation
KEYWORDS: Geo-visualization - 2D animation
SCIENTIFIC DESCRIPTION: Before-and-after image pairs show how entities in a given region have evolved over a specific period of time. Satellite images are a major source of such data, that capture how natural phenomena or human activity impact a geographical area. These images are used both for data analysis and to illustrate the resulting findings to diverse audiences. The simple techniques used to display them, including juxtaposing, swapping and monolithic blending, often fail to convey the underlying phenomenon in a meaningful manner. Baia is a framework to create advanced animated transitions, called animation plans, between before-and-after images. Baia relies on a pixel-based transition model that gives authors much expressive power, while keeping animations for common types of changes easy to create thanks to predefined animation primitives.
FUNCTIONAL DESCRIPTION: Baia is a framework to create advanced animated transitions, called animation plans, between before-and-after satellite images.

Before-and-after image pairs show how entities in a given region have evolved over a specific period of time. Satellite images are a major source of such data, that capture how natural phenomena or human activity impact a geographical area. These images are used both for data analysis and to illustrate the resulting findings to diverse audiences. The simple techniques used to display them, including juxtaposing, swapping and monolithic blending, often fail to convey the underlying phenomenon in a meaningful manner.

Baia relies on a pixel-based transition model that gives authors much expressive power. The animation editor enables authors to easily represent common types of changes thanks to predefined animation primitives and to sequence different changes across time.

RELEASE FUNCTIONAL DESCRIPTION: First public release

- Participants: Maria Jesus Lobo Gunther, Caroline Appert and Emmanuel Pietriga
- Contact: Emmanuel Pietriga
- Publication: Animation Plans for Before-and-After Satellite Images
- URL: http://ilda.saclay.inria.fr/mapmuxing/baia/index.html

5.5. LODAtlas

KEYWORDS: LOD - Linked open data - Semantic Web

SCIENTIFIC DESCRIPTION: The Web of Data is growing fast, as exemplified by the evolution of the Linked Open Data (LOD) cloud over the last ten years. One of the consequences of this growth is that it is becoming increasingly difficult for application developers and end-users to find the datasets that would be relevant to them. Semantic Web search engines, open data catalogs , datasets and frameworks such as LODStats and LOD Laundromat, are all useful but only give partial, even if complementary, views on what datasets are available on the Web. LODAtlas is a portal that enables users to find datasets of interest. Users can make different types of queries about both the datasets' metadata and contents, aggregated from multiple sources. They can then quickly evaluate the matching datasets' relevance, thanks to LODAtlas' summary visualizations of their general metadata, connections and contents.

FUNCTIONAL DESCRIPTION: The Web of Data is growing fast, as exemplified by the evolution of the Linked Open Data (LOD) cloud over the last ten years. One of the consequences of this growth is that it is becoming increasingly difficult for application developers and end-users to find the datasets that would be relevant to them. Semantic Web search engines, open data catalogs, datasets and frameworks such as LODStats and LOD Laundromat, are all useful but only give partial, even if complementary, views on what datasets are available on the Web. LODAtlas is a portal that enables users to find datasets of interest. Users can make different types of queries about both the datasets' metadata and contents, aggregated from multiple sources. They can then quickly evaluate the matching datasets' relevance, thanks to LODAtlas' summary visualizations of their general metadata, connections and contents.

- Participants: Caroline Appert, Marie Destandau, Ioana Manolescu, François Goasdoué, Sejla Cebiric, Hande Gozukan and Emmanuel Pietriga
- Contact: Emmanuel Pietriga
- Publication: Browsing Linked Data Catalogs with LODAtlas
- URL: http://lodatlas.lri.fr

5.6. TouchTokens

KEYWORDS: Tangible interface - HCI

SCIENTIFIC DESCRIPTION: TouchTokens make it possible to easily build interfaces that combine tangible and gestural input using passive tokens and a regular multi-touch surface. The tokens constrain users' grasp, and thus, the relative spatial configuration of fingers on the surface, theoretically making it possible to design algorithms that can recognize the resulting touch patterns. See associated scientific articles below.

FUNCTIONAL DESCRIPTION: TouchTokens allow interface designers to build low-cost tangible interfaces. The technique consists in recognizing multi-touch patterns that are associated with specific passive tokens. Those physical tokens can be made out of any material to get tracked on any touch-sensitive surface. Implementations of the recognizer (in both TUIO and Android) and vector descriptions of the tokens ready for 3D-printing or laser-cutting are available

- Participants: Caroline Appert, Rafael Morales Gonzalez, Emmanuel Pietriga and Gilles Bailly
- Contact: Caroline Appert
- Publications: TouchTokens: Guiding Touch Patterns with Passive Tokens - Passive yet Expressive TouchTokens - Custom-made Tangible Interfaces with TouchTokens
- URL: https://www.lri.fr/~appert/touchtokens/

5.7. Platforms
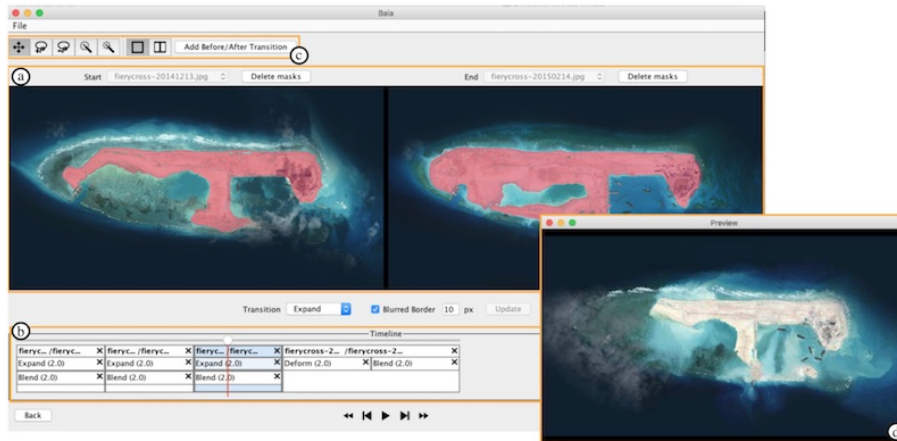
5.7.1. Platform: WILDER

Figure 2. Baia is a framework to create advanced animated transitions between before-and-after satellite images. Before-and-after image pairs show how entities in a given region have evolved over a specific period of time. Baia relies on a pixel-based transition model to convey the underlying phenomenon that caused this evolution in a meaningful manner. The animation editor pictured here enables authors to easily represent common types of changes thanks to predefined animation primitives and to sequence different changes across time.

Figure 3. Multiple asteroid-generated tsunami simulations running simultaneously on the WILDER ultra-wall. The high display capacity of this interactive surface makes it possible to show, for each of the simulations: a planet-wide view showing the propagation of the tsunami on the globe, a close-up on the region of impact, showing a simulation of one or more scalar fields, parameters of the simulation.

Ultra-high-resolution wall-sized displays [39] feature a very high pixel density over a large physical surface. Such platforms have properties that make them well-suited to the visualization of very large datasets. They can represent the data with a high level of detail while at the same time retaining context: users can transition from an overview of the data to a detailed view simply by physically moving in front of the wall display. Wall displays also offer good support for collaborative work, enabling multiple users to simultaneously visualize and interact with the displayed data. To make them interactive, wall-sized displays are increasingly coupled with input devices such as touch frames, motion-tracking systems and wireless multitouch devices, in order to enable multi-device and multi-user interaction with the displayed data. Application areas for such visualization platforms range from the monitoring of complex infrastructures and crisis management situations to tools for the exploratory visualization of scientific data.

WILDER is the latest ultra-high-resolution wall-sized display set up at Inria Saclay, and is one of the nodes of the Digiscope EquipEx. We use this platform for multiple projects, both fundamental HCI research, and research and development activities for specific application areas such as geographical informations systems (Figure 3) and astronomy.

WILDER was used in the projects that led to the following publications this year: [23], [31].

IMAGINE Project-Team

6. New Software and Platforms

6.1. MyCF

My Corporis Fabrica

KEYWORDS: 3D modeling - Simulation - Health - Ontologies - Anatomy - Patientspecific - Medical imaging

FUNCTIONAL DESCRIPTION: Knowledge-based 3D anatomical modeling using MyCF The MyCF software eases the creation of 3D anatomical models for visualization and mechanical simulation. As input, the user provides a list of anatomical entities or functions to simulate, using keywords or navigating in reference 3D model. As output, she gets a 3D model ready to visualize, or to simulate.

- Participants: Ali Hamadi Dicko, Federico Ulliana, François Faure and Olivier Palombi
- Partner: Université Joseph-Fourier
- Contact: Olivier Palombi

6.2. Kino AI

Artificial intelligence for cinematography

KEYWORDS: Video analysis - Post-production

FUNCTIONAL DESCRIPTION: Kino AI is an implementation of the method described in our patent "automatic generation of cinematographic rushes using video processing". Starting from a single ultra high definitiion (UltraHD) recording of a live performance, we track and recognize all actors present on stage and generate one or more rushes suitable for cinematographic editing of a movie.

- Partner: IIIT Hyderabad
- Contact: Rémi Ronfard
- Publications: Multi-Clip Video Editing from a Single Viewpoint - Zooming On All Actors: Automatic Focus+Context Split Screen Video Generation

6.3. Platforms

6.3.1. AANALYSIS

AANALYSIS is a platform developed from 2015 to 2018 as a module of the SALOME platform and as a plugin of SHAPER (a software under development by EDF, CEA and OpenCascade). It processes CAD assemblies to derive symmetry properties, similarities of solids and groups of solids, interface features between solids and is operational on industrial models. The plugin version implements a shape similarity selection feature. The module is connected with a knowledge database MyProductFabrica developed in our group in partnership with GraphiK Inria team. It enables the automatic generation/annotation of functional knowledge from 3D geometry using 350 concepts, 90 relations and more than 100 inferences.

6.3.2. RUMBA

RUMBA is a next-generation 3D animation software targeted to professional animation studios, developed jointly by Mercenaries Engineering, TEAMTO and IMAGINE. Development was funded in part by FUI projects COLLODI 1 and COLLODI 2. RUMBA has been used in production by TEAMTO since 2017. RUMBA will be made commercially available to other animation studio by Mercenaries Engineering in 2019. We are using RUMBA as a platform for developing new algorithms in sketch-based animation, based on our previous work during Martin Guay's PhD thesis. This includes many improvements to allow those methods to work in a professional workflow.

6.3.3. SKY ENGINE

Sky Engine is a realtime game engine developped by Maxime Garcia as part of his PhD thesis, which incorporates several shape modleing and animation tools developped within the team. It is hoped that it will supersede Expressive as a platform for future integration of research results of the team involving real-time, story-driven shape modeling, animation and cinematography.

LOKI Team

6. New Software and Platforms

6.1. ParkEvolution

Longitudinal analysis of fine motor movement in an ecological context for patients with Parkinson disease
KEYWORD: Parkinson disease
FUNCTIONAL DESCRIPTION: The originality of this application relies on the acquisition of data in an ecological context. Thanks to this application that patients download on their personal computer, the data corresponding to cursor displacement on screen and raw input from pointing devices are collected, encrypted and sent to a server. The analysis of this data allows to compute a motor score according to the parameters of movement, in order to identify alterations in fine motor control. We ensure a realistic score based on the important quantity of data collected. This software is written in C++ and runs on Windows. It uses the libpointing library to access raw data from pointing devices.

RELEASE FUNCTIONAL DESCRIPTION: Fixed bugs and developed new features.
NEWS OF THE YEAR: Release of the 1.3.0 version fixing a number of bugs and introducing a number of new small features. An APP request is close of getting approved.

- Participants: Géry Casiez and Laure Fernandez
- Partners: Aix-Marseille Université - CNRS Laboratoire de Psychologie Cognitive - UMR 7290 - Team 'Perception and attention' - Institut de Neurosciences de la Timone
- Contact: Géry Casiez
- URL: http://parkevolution.org/

6.2. liblag

Library implementing latency compensation techniques for interactive systems
KEYWORDS: Interaction - Latency
FUNCTIONAL DESCRIPTION: The library comprises the management of a set of multitouch input devices, the implementation of latency compensation techniques from the state-of-the-art and new latency compensation techniques developed in the project, and a system to handle artificial latency.

The library is developed in C++ using the Qt framework to allow compiling the same code on a wide range of devices and platforms.
NEWS OF THE YEAR: Finished the work on the latency compensation algorithm "TurboTouch predictor" and development of the demonstrator presented at Euratechnologies. Development of an on-line interactive demo available at http://ns.inria.fr/loki/TTp/

- Contact: Géry Casiez
- Publications: Dispositif à affichage prédictif - Next-Point Prediction for Direct Touch Using Finite-Time Derivative Estimation
- URL: http://mjolnir.lille.inria.fr/turbotouch/

MANAO Project-Team

6. New Software and Platforms

6.1. Eigen

KEYWORD: Linear algebra

FUNCTIONAL DESCRIPTION: Eigen is an efficient and versatile C++ mathematical template library for linear algebra and related algorithms. In particular it provides fixed and dynamic size matrices and vectors, matrix decompositions (LU, LLT, LDLT, QR, eigenvalues, etc.), sparse matrices with iterative and direct solvers, some basic geometry features (transformations, quaternions, axis-angles, Euler angles, hyperplanes, lines, etc.), some non-linear solvers, automatic differentiations, etc. Thanks to expression templates, Eigen provides a very powerful and easy to use API. Explicit vectorization is performed for the SSE, AltiVec and ARM NEON instruction sets, with graceful fallback to non-vectorized code. Expression templates allow to perform global expression optimizations, and to remove unnecessary temporary objects.

RELEASE FUNCTIONAL DESCRIPTION: In 2017, we released three revisions of the 3.3 branch with few fixes of compilation and performance regressions, some doxygen documentation improvements, and the addition of transpose, adjoint, conjugate methods to SelfAdjointView to ease writing generic code.

- Participant: Gaël Guennebaud
- Contact: Gaël Guennebaud
- URL: http://eigen.tuxfamily.org/

6.2. Elasticity Skinning

KEYWORD: 3D animation

FUNCTIONAL DESCRIPTION: Geometric skinning techniques are very popular in the industry for their high performances, but fail to mimic realistic deformations. With elastic implicit skinning the skin stretches automatically (without skinning weights) and the vertices distribution is more pleasing. Our approach is more robust, for instance the angle's range of joints is larger than implicit skinning.

This software has been ported as a plugin for the Modo software (The Foundry) in collaboration with Toulouse Tech Transfer. This plugin has been bought by The Foundry, which maintains and sells it.

- Participants: Brian Wyvill, Damien Rohmer, Florian Canezin, Gaël Guennebaud, Loïc Barthe, Marie-Paule Cani, Mathias Paulin, Olivier Gourmel and Rodolphe Vaillant
- Partners: Université de Bordeaux - CNRS - INP Bordeaux - Université de Toulouse - Institut Polytechnique de Grenoble - Ecole Supérieure de Chimie Physique Electronique de Lyon
- Contact: Gaël Guennebaud
- URL: https://www.irit.fr/~Loic.Barthe/transfer.php

MAVERICK Project-Team

6. New Software and Platforms

6.1. Diffusion curves

KEYWORDS: Vector-based drawing - Shading

FUNCTIONAL DESCRIPTION: Diffusion Curves is a vector-based design tool for creating complex shaded images. This prototype is composed of the Windows binary, along with the required shader programs (ie. in source code).

- Participants: Adrien Bousseau, Alexandrina Orzan, David Salesin, Holger Winnemoeller, Joëlle Thollot and Pascal Barla
- Partners: CNRS - LJK - INP Grenoble - Université Joseph-Fourier
- Contact: Joëlle Thollot
- URL: http://maverick.inria.fr/Publications/2008/OBWBTS08/index.php

6.2. GigaVoxels

FUNCTIONAL DESCRIPTION: Gigavoxel is a software platform which goal is the real-time quality rendering of very large and very detailed scenes which couldn't fit memory. Performances permit showing details over deep zooms and walk through very crowdy scenes (which are rigid, for the moment). The principle is to represent data on the GPU as a Sparse Voxel Octree which multiscale voxels bricks are produced on demand only when necessary and only at the required resolution, and kept in a LRU cache. User defined producer lays accross CPU and GPU and can load, transform, or procedurally create the data. Another user defined function is called to shade each voxel according to the user-defined voxel content, so that it is user choice to distribute the appearance-making at creation (for faster rendering) or on the fly (for storageless thin procedural details). The efficient rendering is done using a GPU differential cone-tracing using the scale corresponding to the 3D-MIPmapping LOD, allowing quality rendering with one single ray per pixel. Data is produced in case of cache miss, and thus only whenever visible (accounting for view frustum and occlusion). Soft-shadows and depth-of-field is easily obtained using larger cones, and are indeed cheaper than unblurred rendering. Beside the representation, data management and base rendering algorithm themself, we also worked on realtime light transport, and on quality prefiltering of complex data. Ongoing researches are addressing animation. GigaVoxels is currently used for the quality real-time exploration of the detailed galaxy in ANR RTIGE. Most of the work published by Cyril Crassin (and al.) during his PhD (see http://maverick.inria.fr/Members/Cyril.Crassin/) is related to GigaVoxels. GigaVoxels is available for Windows and Linux under the BSD-3 licence.

- Participants: Cyril Crassin, Eric Heitz, Fabrice Neyret, Jérémy Sinoir, Pascal Guehl and Prashant Goswami
- Contact: Fabrice Neyret
- URL: http://gigavoxels.inrialpes.fr

6.3. GRATIN

FUNCTIONAL DESCRIPTION: Gratin is a node-based compositing software for creating, manipulating and animating 2D and 3D data. It uses an internal direct acyclic multi-graph and provides an intuitive user interface that allows to quickly design complex prototypes. Gratin has several properties that make it useful for researchers and students. (1) it works in real-time: everything is executed on the GPU, using OpenGL, GLSL and/or Cuda. (2) it is easily programmable: users can directly write GLSL scripts inside the interface, or create new C++ plugins that will be loaded as new nodes in the software. (3) all the parameters can be animated using keyframe curves to generate videos and demos. (4) the system allows to easily exchange nodes, group of nodes or full pipelines between people.

- Participants: Pascal Barla and Romain Vergne
- Partner: UJF
- Contact: Romain Vergne
- URL: http://gratin.gforge.inria.fr/

6.4. HQR

High Quality Renderer
KEYWORDS: Lighting simulation - Materials - Plug-in
FUNCTIONAL DESCRIPTION: HQR is a global lighting simulation platform. HQR software is based on the photon mapping method which is capable of solving the light balance equation and of giving a high quality solution. Through a graphical user interface, it reads X3D scenes using the X3DToolKit package developed at Maverick, it allows the user to tune several parameters, computes photon maps, and reconstructs information to obtain a high quality solution. HQR also accepts plugins which considerably eases the developpement of new algorithms for global illumination, those benefiting from the existing algorithms for handling materials, geometry and light sources.

- Participant: Cyril Soler
- Contact: Cyril Soler
- URL: http://artis.imag.fr/~Cyril.Soler/HQR

6.5. libylm

LibYLM
KEYWORD: Spherical harmonics
FUNCTIONAL DESCRIPTION: This library implements spherical and zonal harmonics. It provides the means to perform decompositions, manipulate spherical harmonic distributions and provides its own viewer to visualize spherical harmonic distributions.

- Author: Cyril Soler
- Contact: Cyril Soler
- URL: https://launchpad.net/~csoler-users/+archive/ubuntu/ylm

6.6. MobiNet

KEYWORDS: Co-simulation - Education - Programmation

FUNCTIONAL DESCRIPTION: The MobiNet software allows for the creation of simple applications such as video games, virtual physics experiments or pedagogical math illustrations. It relies on an intuitive graphical interface and language which allows the user to program a set of mobile objects (possibly through a network). It is available in public domain for Linux,Windows and MacOS.

- Participants: Fabrice Neyret, Franck Hétroy-Wheeler, Joëlle Thollot, Samuel Hornus and Sylvain Lefebvre
- Partners: CNRS - LJK - INP Grenoble - Inria - IREM - Cies - GRAVIR
- Contact: Fabrice Neyret
- URL: http://mobinet.imag.fr/index.en.html

6.7. PLANTRAD

KEYWORDS: Bioinformatics - Biology
FUNCTIONAL DESCRIPTION: PlantRad is a software program for computing solutions to the equation of light equilibrium in a complex scene including vegetation. The technology used is hierarchical radiosity with clustering and instantiation. Thanks to the latter, PlantRad is capable of treating scenes with a very high geometric complexity (up to millions of polygons) such as plants or any kind of vegetation scene where a high degree of approximate self-similarity permits a significant gain in memory requirements.

- Participants: Cyril Soler, François Sillion and George Drettakis
- Contact: Cyril Soler

6.8. PROLAND

PROcedural LANDscape
KEYWORDS: Real time - 3D - Realistic rendering - Masses of data - Atmosphere - Ocean
FUNCTIONAL DESCRIPTION: The goal of this platform is the real-time quality rendering and editing of large landscapes. All features can work with planet-sized terrains, for all viewpoints from ground to space. Most of the work published by Eric Bruneton and Fabrice Neyret (see http://evasion.inrialpes.fr/Membres/Eric.Bruneton/) has been done within Proland and integrated in the main branch. Proland is available under the BSD-3 licence.

- Participants: Antoine Begault, Eric Bruneton, Fabrice Neyret and Guillaume Piolet
- Contact: Fabrice Neyret
- URL: https://proland.inrialpes.fr/

6.9. ShwarpIt

KEYWORD: Warping
FUNCTIONAL DESCRIPTION: ShwarpIt is a simple mobile app that allows you to manipulate the perception of shapes in images. Slide the ShwarpIt slider to the right to make shapes appear rounder. Slide it to the left to make shapes appear more flat. The Scale slider gives you control on the scale of the warping deformation.

- Contact: Georges-Pierre Bonneau
- URL: http://bonneau.meylan.free.fr/ShwarpIt/ShwarpIt.html

6.10. Vrender

FUNCTIONAL DESCRIPTION: The VRender library is a simple tool to render the content of an OpenGL window to a vectorial device such as Postscript, XFig, and soon SVG. The main usage of such a library is to make clean vectorial drawings for publications, books, etc.

In practice, VRender replaces the z-buffer based hidden surface removal of OpenGL by sorting the geometric primitives so that they can be rendered in a back-to-front order, possibly cutting them into pieces to solve cycles.

VRender is also responsible for the vectorial snapshot feature of the QGLViewer library.

- Participant: Cyril Soler
- Contact: Cyril Soler
- URL: http://artis.imag.fr/Software/VRender/

6.11. X3D TOOLKIT

X3D Development pateform
FUNCTIONAL DESCRIPTION: X3DToolkit is a library to parse and write X3D files, that supports plugins and extensions.

- Participants: Gilles Debunne and Yannick Le Goc
- Contact: Cyril Soler
- URL: http://artis.imag.fr/Software/X3D/

MFX Team (section vide)

<h2 style="text-align:center; color:red;">MIMETIC Project-Team</h2>

6. New Software and Platforms

6.1. AsymGait

Asymmetry index for clinical gait analysis based on depth images

KEYWORDS: Motion analysis - Kinect - Clinical analysis

SCIENTIFIC DESCRIPTION: The system uses depth images delivered by the Microsoft Kinect to retrieve the gait cycles first. To this end it is based on a analyzing the knees trajectories instead of the feet to obtain more robust gait event detection. Based on these cycles, the system computes a mean gait cycle model to decrease the effect of noise of the system. Asymmetry is then computed at each frame of the gait cycle as the spatial difference between the left and right parts of the body. This information is computed for each frame of the cycle.

FUNCTIONAL DESCRIPTION: AsymGait is a software package that works with Microsoft Kinect data, especially depth images, in order to carry-out clinical gait analysis. First it identifies the main gait events using the depth information (footstrike, toe-off) to isolate gait cycles. Then it computes a continuous asymmetry index within the gait cycle. Asymmetry is viewed as a spatial difference between the two sides of the body.

- Participants: Edouard Auvinet and Franck Multon
- Contact: Franck Multon

6.2. Cinematic Viewpoint Generator

KEYWORD: 3D animation

FUNCTIONAL DESCRIPTION: The software, developed as an API, provides a mean to automatically compute a collection of viewpoints over one or two specified geometric entities, in a given 3D scene, at a given time. These viewpoints satisfy classical cinematographic framing conventions and guidelines including different shot scales (from extreme long shot to extreme close-up), different shot angles (internal, external, parallel, apex), and different screen compositions (thirds,fifths, symmetric of di-symmetric). The viewpoints allow to cover the range of possible framings for the specified entities. The computation of such viewpoints relies on a database of framings that are dynamically adapted to the 3D scene by using a manifold parametric representation and guarantee the visibility of the specified entities. The set of viewpoints is also automatically annotated with cinematographic tags such as shot scales, angles, compositions, relative placement of entities, line of interest.

- Participants: Christophe Lino, Emmanuel Badier and Marc Christie
- Partners: Université d'Udine - Université de Nantes
- Contact: Marc Christie

6.3. Directors Lens Motion Builder

KEYWORDS: Previzualisation - Virtual camera - 3D animation

FUNCTIONAL DESCRIPTION: Directors Lens Motion Builder is a software plugin for Autodesk's Motion Builder animation tool. This plugin features a novel workflow to rapidly prototype cinematographic sequences in a 3D scene, and is dedicated to the 3D animation and movie previsualization industries. The workflow integrates the automated computation of viewpoints (using the Cinematic Viewpoint Generator) to interactively explore different framings of the scene, proposes means to interactively control framings in the image space, and proposes a technique to automatically retarget a camera trajectory from one scene to another while enforcing visual properties. The tool also proposes to edit the cinematographic sequence and export the animation. The software can be linked to different virtual camera systems available on the market.

- Participants: Christophe Lino, Emmanuel Badier and Marc Christie
- Partner: Université de Rennes 1
- Contact: Marc Christie

6.4. Kimea

Kinect IMprovement for Egronomics Assessment

KEYWORDS: Biomechanics - Motion analysis - Kinect

SCIENTIFIC DESCRIPTION: Kimea consists in correcting skeleton data delivered by a Microsoft Kinect in an ergonomics purpose. Kimea is able to manage most of the occlultations that can occur in real working situation, on workstations. To this end, Kimea relies on a database of examples/poses organized as a graph, in order to replace unreliable body segments reconstruction by poses that have already been measured on real subject. The potential pose candidates are used in an optimization framework.

FUNCTIONAL DESCRIPTION: Kimea gets Kinect data as input data (skeleton data) and correct most of measurement errors to carry-out ergonomic assessment at workstation.

- Participants: Franck Multon, Hubert Shum and Pierre Plantard

- Partner: Faurecia

- Contact: Franck Multon

- Publications: Usability of corrected Kinect measurement for ergonomic evaluation in constrained environment - Validation of an ergonomic assessment method using Kinect data in real workplace conditions - Ergonomics Measurements using Kinect with a Pose Correction Framework - Filtered Pose Graph for Efficient Kinect Pose Reconstruction - Reliability of Kinect measurements for assessing the movement of operators in ergonomic studies

6.5. Populate

KEYWORDS: Behavior modeling - Agent - Scheduling

SCIENTIFIC DESCRIPTION: The software provides the following functionalities:

- A high level XML dialect that is dedicated to the description of agents activities in terms of tasks and sub activities that can be combined with different kind of operators: sequential, without order, interlaced. This dialect also enables the description of time and location constraints associated to tasks.

- An XML dialect that enables the description of agent's personal characteristics.

- An informed graph describes the topology of the environment as well as the locations where tasks can be performed. A bridge between TopoPlan and Populate has also been designed. It provides an automatic analysis of an informed 3D environment that is used to generate an informed graph compatible with Populate.

- The generation of a valid task schedule based on the previously mentioned descriptions.

With a good configuration of agents characteristics (based on statistics), we demonstrated that tasks schedules produced by Populate are representative of human ones. In conjunction with TopoPlan, it has been used to populate a district of Paris as well as imaginary cities with several thousands of pedestrians navigating in real time.

FUNCTIONAL DESCRIPTION: Populate is a toolkit dedicated to task scheduling under time and space constraints in the field of behavioral animation. It is currently used to populate virtual cities with pedestrian performing different kind of activities implying travels between different locations. However the generic aspect of the algorithm and underlying representations enable its use in a wide range of applications that need to link activity, time and space. The main scheduling algorithm relies on the following inputs: an informed environment description, an activity an agent needs to perform and individual characteristics of this agent. The algorithm produces a valid task schedule compatible with time and spatial constraints imposed by the activity description and the environment. In this task schedule, time intervals relating to travel and task fulfillment are identified and locations where tasks should be performed are automatically selected.

- Participants: Carl-Johan Jorgensen and Fabrice Lamarche

- Contact: Fabrice Lamarche

6.6. The Theater

KEYWORDS: 3D animation - Interactive Scenarios
FUNCTIONAL DESCRIPTION: The Theater is a software framework to develop interactive scenarios in virtual 3D environements. The framework provides means to author and orchestrate 3D character behaviors and simulate them in real-time. The tools provides a basis to build a range of 3D applications, from simple simulations with reactive behaviors, to complex storytelling applications including narrative mechanisms such as flashbacks.

- Participant: Marc Christie
- Contact: Marc Christie

6.7. CusToM

Customizable Toolbox for Musculoskeletal simulation
KEYWORDS: Biomechanics - Dynamic Analysis - Kinematics - Simulation - Mechanical multi-body systems
SCIENTIFIC DESCRIPTION: The present toolbox aims at performing a motion analysis thanks to an inverse dynamics method.

Before performing motion analysis steps, a musculoskeletal model is generated. Its consists of, first, generating the desire anthropometric model thanks to models libraries. The generated model is then kinematical calibrated by using data of a motion capture. The inverse kinematics step, the inverse dynamics step and the muscle forces estimation step are then successively performed from motion capture and external forces data. Two folders and one script are available on the toolbox root. The Main script collects all the different functions of the motion analysis pipeline. The Functions folder contains all functions used in the toolbox. It is necessary to add this folder and all the subfolders to the Matlab path. The Problems folder is used to contain the different study. The user has to create one subfolder for each new study. Once a new musculoskeletal model is used, a new study is necessary. Different files will be automaticaly generated and saved in this folder. All files located on its root are related to the model and are valuable whatever the motion considered. A new folder will be added for each new motion capture. All files located on a folder are only related to this considered motion.
FUNCTIONAL DESCRIPTION: Inverse kinematics Inverse dynamics Muscle forces estimation External forces prediction

- Participants: Antoine Muller, Charles Pontonnier and Georges Dumont
- Contact: Antoine Muller

6.8. MotionGraphVR

KEYWORDS: Virtual reality - Motion capture - Movement analysis
FUNCTIONAL DESCRIPTION: MotionGraphVR is a tool enabling users to automatically create motion graphs in Unity. It is particularly targeting Virtual Reality applications, where with the development of Head Mounted Displays users are now unable to see their real body unless they use expensive motion capture system, or animation techniques (e.g., Inverse Kinematics) which suffer from a lack of visual realism. To lever these limitations, MotionGraphVR automatically builds a graph of human motions from a set of examples captured on a real actor, and identify which motion path is the graph is closest to the user's actions. Additionally, this plugin also provides analysing tools to allow developers of VR applications to visualise similarities between movements to use in their applications before seamlessly connecting them in Motion Graphs.

- Participants: Tiffany Luong, Ludovic Hoyet and Fernando Argelaguet Sanz
- Contact: Ludovic Hoyet

6.9. Platforms

6.9.1. Immerstar Platform

Participants: Georges Dumont [contact], Ronan Gaugne, Anthony Sorel, Richard Kulpa.

With the two platforms of virtual reality, Immersia (http://www.irisa.fr/immersia/) and Immermove (http://m2slab.com/index.php/facilities-4/), grouped under the name Immerstar, the team has access to high level scientific facilities. This equipment benefits the research teams of the center and has allowed them to extend their local, national and international collaborations. The Immerstar platform is granted by a Inria CPER funding for 2015-2019 that enables important evolutions of the equipment. In 2016, the first technical evolutions have been decided and, in 2017, these evolutions have been implemented. On the one side, for Immermove, a third face to the immersive space was added. Moreover, 23 new Qualisys cameras were bought to complete the Vicon motion capture system for a total budget of 160k€half funded by Rennes Métropole. Both systems can interoperate to cover all the gymnasium but can also be used separately. On the other side, for Immersia, the installation of WQXGA laser projectors with augmented global resolution, of a new tracking system with higher frequency and of new computers for simulation and image generation in 2017. In 2018, a Scale One haptic device has been installed,. It allows, as in the CPER proposal, single-handed or dual-handed haptic feedback in the full space covered by Immersia, with the possibility of carrying the user (see Figure 2).
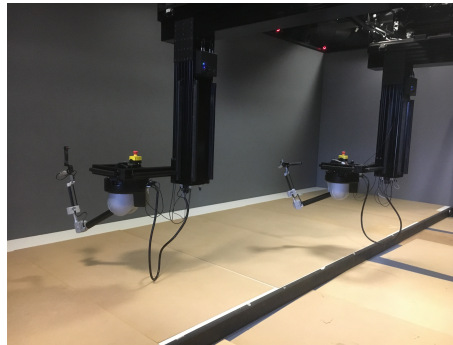

Figure 4. Upgrade of the Immersia platform with the Scale-One Haptic device enabling single-handed or dual-handed haptic feedback in the full space covered by Immersia, with the possibility of carrying the user.

<h1 style="text-align: center; color: red;">POTIOC Project-Team</h1>

6. New Software and Platforms

6.1. Aïana

KEYWORD: Multimedia player

FUNCTIONAL DESCRIPTION: This software aims to make accessible the playing of a MOOC composed of various information flows (boards, videos, subtitles ...). It is not intended to be "reserved" for people with disabilities but rather to be open to as many as possible by allowing each user to adapt the interface, and therefore the use, to its users own capabilities and needs.

- Authors: Damien Caselli, Pierre-Antoine Cinquin, Pascal Guitton and Hélène Sauzéon
- Partner: Université de Bordeaux
- Contact: Pascal Guitton
- Publications: Towards Truly Accessible MOOCs for Persons with Cognitive Disabilities: Design and Field Assessment - Online e-learning and cognitive disabilities: A systematic review

6.2. HybridOptics : Hybrid Optical Platform

KEYWORDS: Augmented reality - Education - Tangible interface

FUNCTIONAL DESCRIPTION: The software platform - gets the values of the sensors - computes in real-time the result of the simulation - generates pedagogical supports that are directly linked to the simulation (projected on the work table) - allows the user to control several parameters from a dedicated application on a tablet

- Participants: Benoît Coulais, Lionel Canioni, Bruno Bousquet, Martin Hachet and Jean-Paul Guillet
- Contact: Martin Hachet
- URL: https://project.inria.fr/hobit/

6.3. Platforms

6.3.1. HOBIT

In 2018, we have continued working on the HOBIT platform dedicated to teaching and training of Optics at University. We have notably improved the hardware side, as illustrated in Figure 3 .
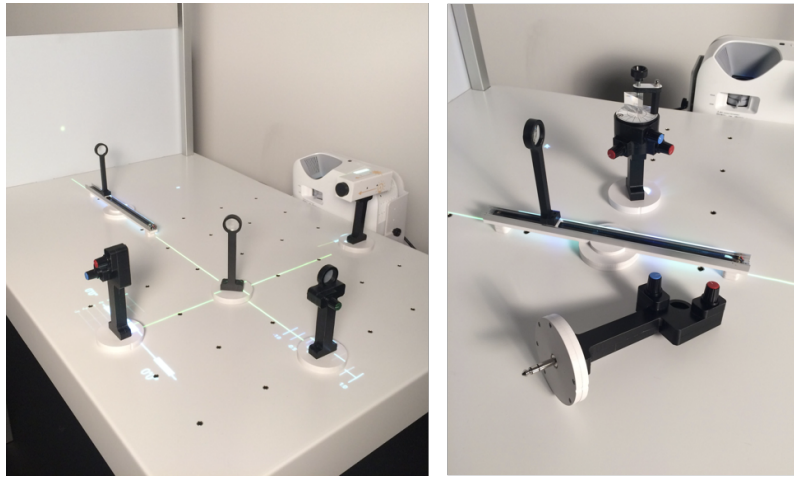
Figure 3. The new version of HOBIT. Users can easily plug fake optical components (e.g. source lights, mirrors and lens) anywhere on the table to build their optical experiment.

TITANE Project-Team

6. New Software and Platforms

6.1. CGAL Barycentric_coordinates_2

Module CGAL : Barycentric coordinates 2D
KEYWORD: Computational geometry
FUNCTIONAL DESCRIPTION: This package offers an efficient and robust implementation of two-dimensional closed-form generalized barycentric coordinates defined for simple two-dimensional polygons.

- Participants: Dmitry Anisimov and Pierre Alliez
- Contact: Pierre Alliez

6.2. dtk-nurbs-probing

KEYWORDS: Algorithm - CAD - Numerical algorithm - Geometric algorithms
FUNCTIONAL DESCRIPTION: This library offers tools for computing intersection between linear primitives and the constitutive elements of CAD objects (curves and surfaces). It is thus possible to compute intersections between a linear primitive with a trimmed or untrimmed NURBS surface, as well with Bezier surfaces. It is also possible, in the xy plane, to compute the intersections between linear primitives and NURBS curves as well as Bezier curves.

- Participants: Come Le Breton, Laurent Busé and Pierre Alliez
- Contact: Come Le Breton

6.3. MeshMantics

KEYWORDS: Classification - 3D modeling
FUNCTIONAL DESCRIPTION: This software component enables the classification of surface meshes in accordance to common outdoor urban classes such as ground, facades, walls, roofs and vegetation.

- Participants: Florent Lafarge, Pierre Alliez and Yannick Verdié
- Contact: Pierre Alliez

6.4. Module CGAL : Point Set Processing

KEYWORD: Geometry Processing
FUNCTIONAL DESCRIPTION: This CGAL component implements methods to analyze and process unorganized point sets. The input is an unorganized point set, possibly with normal attributes (unoriented or oriented). The point set can be analyzed to measure its average spacing, and processed through functions devoted to the simplification, outlier removal, smoothing, normal estimation, normal orientation and feature edges estimation.

- Participants: Clément Jamin, Laurent Saboret and Pierre Alliez
- Contact: Pierre Alliez
- URL: http://doc.cgal.org/latest/Point_set_processing_3/index.html#Chapter_Point_Set_Processing

6.5. Module CGAL : Scale space surface reconstruction

KEYWORD: Geometric algorithms

SCIENTIFIC DESCRIPTION: This CGAL package implements a surface reconstruction method which takes as input an unordered point set and computes a triangulated surface mesh interpolating the point set. We assume that the input points were sampled from the surface of an object. The method can also process point sets sampled from the interior of the object, although we cannot provide guarantees on the output. This method can handle a decent amount of noise and outliers. The point set may greatly undersample the object in occluded regions, although no surface will be reconstructed to fill these regions.

FUNCTIONAL DESCRIPTION: This method allows to reconstruct a surface that interpolates a set of 3D points. This method provides an efficient alternative to the Poisson surface reconstruction method. The main difference in output is that this method reconstructs a surface that interpolates the point set (as opposed to approximating the point set). How the surface connects the points depends on a scale variable, which can be estimated semi-automatically.

- Participants: Pierre Alliez and Thijs Van Lankveld
- Contact: Pierre Alliez

6.6. Skeleton-Blockers

Skeleton-Blockers data-structure
KEYWORDS: C++ - Mesh - Triangulation - Topology - 3D
FUNCTIONAL DESCRIPTION: Skeleton-Blockers is a compact, efficient and generic data-structure that can represent any simplicial complex. The implementation is in C++11.

- Participant: David Salinas
- Contact: David Salinas
- URL: https://project.inria.fr/gudhi/software/

6.7. Structure-preserving decimation

KEYWORDS: Mesh - 3D - Multi-View reconstruction
FUNCTIONAL DESCRIPTION: Structure-preserving decimation is a software that can simplify 3D meshes while preserving some of their structure. Simplification can be done either with a command line or with a graphical user interface that allows to combine several operations including several simplification methods.

- Participants: David Salinas, Florent Lafarge and Pierre Alliez
- Contact: David Salinas

ALMAnaCH Team

5. New Software and Platforms

5.1. Enqi

- Author: Benoît Sagot
- Contact: Benoît Sagot

5.2. SYNTAX

KEYWORD: Parsing

FUNCTIONAL DESCRIPTION: Syntax system includes various deterministic and non-deterministic CFG parser generators. It includes in particular an efficient implementation of the Earley algorithm, with many original optimizations, that is used in several of Alpage's NLP tools, including the pre-processing chain Sx Pipe and the LFG deep parser SxLfg . This implementation of the Earley algorithm has been recently extended to handle probabilistic CFG (PCFG), by taking into account probabilities both during parsing (beam) and after parsing (n-best computation).

- Participants: Benoît Sagot and Pierre Boullier
- Contact: Pierre Boullier
- URL: http://syntax.gforge.inria.fr/

5.3. FRMG

KEYWORDS: Parsing - French

FUNCTIONAL DESCRIPTION: FRMG is a large-coverage linguistic meta-grammar of French. It can be compiled (using MGCOMP) into a Tree Adjoining Grammar, which, in turn, can be compiled (using DyALog) into a parser for French.

- Participant: Éric Villemonte De La Clergerie
- Contact: Éric De La Clergerie
- URL: http://mgkit.gforge.inria.fr/

5.4. MElt

Maximum-Entropy lexicon-aware tagger

KEYWORD: Part-of-speech tagger

FUNCTIONAL DESCRIPTION: MElt is a freely available (LGPL) state-of-the-art sequence labeller that is meant to be trained on both an annotated corpus and an external lexicon. It was developed by Pascal Denis and Benoît Sagot within the Alpage team, a joint Inria and Université Paris-Diderot team in Paris, France. MElt allows for using multiclass Maximum-Entropy Markov models (MEMMs) or multiclass perceptrons (multitrons) as underlying statistical devices. Its output is in the Brown format (one sentence per line, each sentence being a space-separated sequence of annotated words in the word/tag format).

MElt has been trained on various annotated corpora, using Alexina lexicons as source of lexical information. As a result, models for French, English, Spanish and Italian are included in the MElt package.

MElt also includes a normalization wrapper aimed at helping processing noisy text, such as user-generated data retrieved on the web. This wrapper is only available for French and English. It was used for parsing web data for both English and French, respectively during the SANCL shared task (Google Web Bank) and for developing the French Social Media Bank (Facebook, twitter and blog data).

- Contact: Benoît Sagot
- URL: https://team.inria.fr/almanach/melt/

5.5. dyalog-sr

KEYWORDS: Parsing - Deep learning - Natural language processing

FUNCTIONAL DESCRIPTION: DyALog-SR is a transition-based dependency parser, built on top of DyALog system. Parsing relies on dynamic programming techniques to handle beams. Supervised learning exploit a perceptron and aggressive early updates. DyALog-SR can handle word lattice and produce dependency graphs (instead of basic trees). It was tested during several shared tasks (SPMRL'2013 and SEMEVAL'2014). It achieves very good accuracy on French TreeBank, alone or by coupling with FRMG parser. In 2017, DyALog-SR has been extended into DyALog-SRNN by adding deep neuronal layers implemented with the Dynet library. The new version has participated to the evaluation campaigns CONLL UD 2017 (on more than 50 languages) and EPE 2017.

- Contact: Éric De La Clergerie

5.6. Crapbank

French Social Media Bank

KEYWORDS: Treebank - User-generated content

FUNCTIONAL DESCRIPTION: The French Social Media Bank is a treebank of French sentences coming from various social media sources (Twitter(c), Facebook(c)) and web forums (JeuxVidéos.com(c), Doctissimo.fr(c)). It contains different kind of linguistic annotations: - part-of-speech tags - surface syntactic representations (phrase-based representations) as well as normalized form whenever necessary.

- Contact: Djamé Seddah

5.7. DyALog

KEYWORD: Logic programming

FUNCTIONAL DESCRIPTION: DyALog provides an environment to compile and execute grammars and logic programs. It is essentially based on the notion of tabulation, i.e. of sharing computations by tabulating traces of them. DyALog is mainly used to build parsers for Natural Language Processing (NLP). It may nevertheless be used as a replacement for traditional PROLOG systems in the context of highly ambiguous applications where sub-computations can be shared.

- Participant: Éric Villemonte De La Clergerie
- Contact: Éric Villemonte De La Clergerie
- URL: http://dyalog.gforge.inria.fr/

5.8. SxPipe

KEYWORD: Surface text processing

SCIENTIFIC DESCRIPTION: Developed for French and for other languages, Sx Pipe includes, among others, various named entities recognition modules in raw text, a sentence segmenter and tokenizer, a spelling corrector and compound words recognizer, and an original context-free patterns recognizer, used by several specialized grammars (numbers, impersonal constructions, quotations...). It can now be augmented with modules developed during the former ANR EDyLex project for analysing unknown words, this involves in particular (i) new tools for the automatic pre-classification of unknown words (acronyms, loan words...) (ii) new morphological analysis tools, most notably automatic tools for constructional morphology (both derivational and compositional), following the results of dedicated corpus-based studies. New local grammars for detecting new types of entities and improvement of existing ones, developed in the context of the PACTE project, will soon be integrated within the standard configuration.

FUNCTIONAL DESCRIPTION: SxPipe is a modular and customizable processing chain dedicated to applying to raw corpora a cascade of surface processing steps (tokenisation, wordform detection, non-deterministic spelling correction. . .). It is used as a preliminary step before ALMAnaCH's parsers (e.g., FRMG) and for surface processing (named entities recognition, text normalization, unknown word extraction and processing...).

- Participants: Benoît Sagot, Djamé Seddah and Éric Villemonte De La Clergerie
- Contact: Benoît Sagot
- URL: http://lingwb.gforge.inria.fr/

5.9. Mgwiki

KEYWORDS: Parsing - French
FUNCTIONAL DESCRIPTION: Mgwiki is a linguistic wiki that may used to discuss linguistic phenomena with the possibility to add annotated illustrative sentences. The work is essentially devoted to the construction of an instance for documenting and discussing FRMG, with the annotations of the sentences automatically provided by parsing them with FRMG. This instance also offers the possibility to parse small corpora with FRMG and an interface of visualization of the results. Large parsed corpora (like French Wikipedia or Wikisource) are also available. The parsed corpora can also be queried through the use of the DPath language.

- Participant: Éric Villemonte De La Clergerie
- Contact: Éric Villemonte De La Clergerie
- URL: http://alpage.inria.fr/frmgwiki/

5.10. WOLF

WOrdnet Libre du Français (Free French Wordnet)
KEYWORDS: WordNet - French - Semantic network - Lexical resource
FUNCTIONAL DESCRIPTION: The WOLF (Wordnet Libre du Français, Free French Wordnet) is a free semantic lexical resource (wordnet) for French.

The WOLF has been built from the Princeton WordNet (PWN) and various multilingual resources.

- Contact: Benoît Sagot
- URL: http://alpage.inria.fr/~sagot/wolf-en.html

5.11. vera

KEYWORD: Text mining
FUNCTIONAL DESCRIPTION: Automatic analysis of answers to open-ended questions based on NLP and statistical analysis and visualisation techniques (vera is currently restricted to employee surveys).

- Participants: Benoît Sagot and Dimitri Tcherniak
- Partner: Verbatim Analysis
- Contact: Benoît Sagot

5.12. Alexina

Atelier pour les LEXiques INformatiques et leur Acquisition
KEYWORD: Lexical resource
FUNCTIONAL DESCRIPTION: Alexina is ALMAnaCH's framework for the acquisition and modeling of morphological and syntactic lexical information. The first and most advanced lexical resource developed in this framework is the Lefff, a morphological and syntactic lexicon for French.

- Participant: Benoît Sagot
- Contact: Benoît Sagot
- URL: http://gforge.inria.fr/projects/alexina/

5.13. FQB

French QuestionBank

KEYWORD: Treebank

FUNCTIONAL DESCRIPTION: The French QuestionBanks is a corpus of around 2000 questions coming from various domains (TREC data set, French governmental organisation, NGOs, etc..) it contains different kind of annotations - morpho-syntactic ones (POS, lemmas) - surface syntaxe (phrase based and dependency structures) with long-distance dependency annotations.

The TREC part is aligned with the English QuestionBank (Judge et al, 2006).

- Contact: Djamé Seddah

5.14. Sequoia corpus

KEYWORD: Treebank

FUNCTIONAL DESCRIPTION: The Sequoia corpus contains French sentences, annotated with various linguistic information: - parts-of-speech - surface syntactic representations (both constituency trees and dependency trees) - deep syntactic representations (which are deep syntactic dependency graphs)

- Contact: Djamé Seddah

<p style="text-align:center;color:red;">COML Team</p>

5. New Software and Platforms

5.1. abkhazia

KEYWORDS: Speech recognition - Speech-text alignment

FUNCTIONAL DESCRIPTION: The Abkhazia sofware makes it easy to obtain simple baselines for supervised ASR (using Kaldi) and ABX tasks (using ABXpy) on the large corpora of speech recordings typically used in speech engineering, linguistics or cognitive science research.

- Contact: Emmanuel Dupoux
- URL: https://github.com/bootphon/abkhazia

5.2. TDE

Term Discovery Evaluation

KEYWORDS: NLP - Speech recognition - Speech

SCIENTIFIC DESCRIPTION: This toolbox allows the user to judge of the quality of a word discovery algorithm. It evaluates the algorithms on these criteria : - Boundary : efficiency of the algorithm to found the actual boundaries of the words - Group : efficiency of the algorithm to group similar words - Token/Type: efficiency of the algorithm to find all words from the corpus (types), and to find all occurences (token) of these words. - NED : Mean of the edit distance across all the word pairs found by the algorithm - Coverage : efficiency of the algorithm to find every discoverable phone in the corpus

FUNCTIONAL DESCRIPTION: Toolbox to evaluate algorithms that segment speech into words. It allows the user to evaluate the efficiency of algorithms to segment speech into words, and create clusters of similar words.

- Contact: Emmanuel Dupoux
- URL: https://github.com/bootphon/TDE

5.3. ABXpy

KEYWORDS: Evaluation - Speech recognition - Machine learning

FUNCTIONAL DESCRIPTION: The ABX package gives a performance score to speech recognition systems by measuring their capacity to discriminate linguistic contrasts (accents, phonemes, speakers, etc...)

- Contact: Emmanuel Dupoux
- URL: https://github.com/bootphon/ABXpy

5.4. h5features

KEYWORD: File format

FUNCTIONAL DESCRIPTION: The h5features python package provides easy to use and efficient storage of large features data on the HDF5 binary file format.

- Contact: Emmanuel Dupoux
- URL: https://github.com/bootphon/h5features

<p align="center" style="color:red">MULTISPEECH Project-Team</p>

6. New Software and Platforms

6.1. dnnsep

Multichannel audio source separation with deep neural networks

KEYWORDS: Audio - Source Separation - Deep learning

SCIENTIFIC DESCRIPTION: dnnsep is the only source separation software relying on multichannel Wiener filtering based on deep learning. Deep neural networks are used to initialize and reestimate the power spectrum of the sources at every iteration of an expectation-maximization (EM) algorithm. This results in state-of-the-art separation quality for both speech and music.

FUNCTIONAL DESCRIPTION: Combines deep neural networks and multichannel signal processing for speech enhancement and separation of musical recordings.

RELEASE FUNCTIONAL DESCRIPTION: This version derives from version 1.0 (not 1.9). Differences concerns the use of a bidirectional long short-term memory (BLSTM) neural network, smoothing of the multichannel Wiener filter (MWF) over time and frequency, usage of the principal component of the MWF filter, adding a new generalized eigenvector beamformer with blind analytical normalization (GEVB) filter, and normalizing the training and test signals.

- Participants: Aditya Nugraha, Emmanuel Vincent and Antoine Liutkus
- Contact: Emmanuel Vincent

6.2. Dynalips-Player

High realistic lip synchronization for 3d animated characters

KEYWORDS: 3D animation - Graphics - Speech Synthesis

FUNCTIONAL DESCRIPTION: Dynalips provides a solution to synchronize precisely and automatically the movements of the lips of a 3D character with speech (we address 3D animation movies and video games). We have developed a demonstrator that illustrates the whole process: from audio + text to the generation of the animation trajectory, and controlling the animation of a 3D model (e.g. an avatar). The demonstrator is composed mainly by the player developed in Unity 3D (but can be used with any other system) and plays the animation synchronously with speech in realtime. It is possible to generate an animation for Autodesk Maya 3D.

NEWS OF THE YEAR: The whole lip-sync demonstrator is fully operational. From text and recorded speech, the system allows animating two different 3D models. The player is running on Unity 3D.

- Partners: Université de Lorraine - Sayens (SATT Grand Est)
- Contact: Slim Ouni
- URL: http://www.dynalips.com

6.3. KATS

Kaldi-based Automatic Transcription System

KEYWORD: Speech recognition

FUNCTIONAL DESCRIPTION: KATS is a multipass system for transcribing audio data, and in particular radio or TV shows in French, English or Arabic. It is based on the Kaldi speech recognition tools. It relies on Deep Neural Network (DNN) modeling for speech detection and acoustic modeling of the phones (speech sounds). Higher order statistical language models and recurrent neural network language models can be used for improving performance through rescoring of multiple hypotheses.

NEWS OF THE YEAR: New models have been trained for British English and evaluated on MGB data

- Contact: Dominique Fohr

6.4. VisArtico

Visualization of multimodal speech data

KEYWORDS: Data visualization - 3D movement - Speech processing - Videos

SCIENTIFIC DESCRIPTION: VisArtico is a multimodal data visualization software acquired by several systems: articulograph, motion capture, depth camera. This software makes it possible to visualize the positions of real or virtual sensors and to animate them simultaneously with acoustics. Regarding the articulatory data, the user has the possibility to visualise the contour of the tongue and the lips. It also makes it possible to find the midsagittal plane of the speaker, and to deduce the position of the palate, if this information is absent during the acquisition. The software makes it possible to display the segmentation at the level of sentences, words or phonemes. The goal is to provide an effective multimodal data visualization tool that can be useful to anyone studying speech production, audio-visual synthesis, or animation in a more general way.

FUNCTIONAL DESCRIPTION: VisArtico is a user-friendly software which allows visualizing multimodal data acquired by several systems : an articulograph (AG500, AG501 or NDI Wave), motion capture system, depth camera. This visualization software has been designed so that it can directly use the data provided by the different systems to display the spatial and temporal positions of the sensors (real and virtual), synchronized with the corresponding acoustic recordings. Moreover, for articulatory data, VisArtico not only allows viewing the sensors but also enriches the visual information by indicating clearly and graphically the data for the tongue, lips and jaw. Finally, it is possible to generate a movie for any articulatory-acoustic sequence. This software can be useful for researchers in speech production, audiovisual speech synthesis or articulatory speech analysis.

RELEASE FUNCTIONAL DESCRIPTION: The main improvement in this version is the ability to view a video that was recorded along with the articulatory or motion capture data. The software also allows for automatic speech segmentation.

NEWS OF THE YEAR: This year, we have added the possibility to visualize a video simultaneously with the multimodal data and the acoustic data. Several bugs have been fixed.

- Participants: Ilef Ben Farhat, Loïc Mangeonjean and Slim Ouni
- Partners: CNRS - Université de Lorraine
- Contact: Slim Ouni
- Publication: VisArtico: a visualization tool for articulatory data
- URL: http://visartico.loria.fr

6.5. Xarticulators

KEYWORDS: Medical imaging - Natural language processing

FUNCTIONAL DESCRIPTION: The Xarticulators software is intended to delineate contours of speech articulators in X-ray and MR images, construct articulatory models and synthesize speech from X-ray films. This software provides tools to track contours automatically, semi-automatically or by hand, to make the visibility of contours easier, to add anatomical landmarks to speech articulators and to synchronize images with the sound. In addition we also added the possibility of processing digitized manual delineation results made on sheets of papers when no software is available. Xarticulators also enables the construction of adaptable linear articulatory models from the X-ray or MR images and incorporates acoustic simulation tools to synthesize speech signals from the vocal tract shape. Recent work was on the possibility of synthesizing speech from 2D-MRI films, and on the construction of better articulatory models for the velum, lips and epiglottis.

RELEASE FUNCTIONAL DESCRIPTION: The new version allows MRI films to be processed and, above all, it offers a better transition from the shape of the vocal tract to the area function, which corresponds to an approximation of the vocal tract using a series of elementary tubes from the glottis to the lips.

NEWS OF THE YEAR: Improvements to the articulatory model which now takes into account "small" filiform articulators such as the epiglottis and velum using models using the central line. Improvement of the transition from the medio-sagittal 2D form of the vocal tract to the function of area.

- Contact: Yves Laprie
- Publication: Articulatory model of the epiglottis

PANAMA Project-Team

6. New Software and Platforms

6.1. FAuST

KEYWORDS: Learning - Sparsity - Fast transform - Multilayer sparse factorisation

SCIENTIFIC DESCRIPTION: FAuST allows to approximate a given dense matrix by a product of sparse matrices, with considerable potential gains in terms of storage and speedup for matrix-vector multiplications.

FUNCTIONAL DESCRIPTION: Faust 1.x contains Matlab routines to reproduce experiments of the PANAMA team on learned fast transforms.

Faust 2.x contains a C++ implementation with Matlab / Python wrappers (work in progress).

NEWS OF THE YEAR: A Software Development Initiative (ADT REVELATION) started in April 2018 for the maturation of FAuST. A first step achieved this year was to complete and robustify Matlab wrappers, to code Python wrappers with the same functionality, and to setup a continuous integration process. A second step was to simplify the parameterization of the main algorithms. The roadmap for next year includes showcasing examples and optimizing computational efficiency. – In 2017, new Matlab code for fast approximate Fourier Graph Transforms have been included. based on the approach described in the papers:

-Luc Le Magoarou, Rémi Gribonval, "Are There Approximate Fast Fourier Transforms On Graphs?", ICASSP 2016 .

-Luc Le Magoarou, Rémi Gribonval, Nicolas Tremblay, "Approximate fast graph Fourier transforms via multi-layer sparse approximations", IEEE Transactions on Signal and Information Processing over Networks,2017.

- Participants: Luc Le Magoarou, Nicolas Tremblay, Rémi Gribonval, Nicolas Bellot, Adrien Leman and Hakim Hadj-Djilani

- Contact: Rémi Gribonval

- Publications: Approximate fast graph Fourier transforms via multi-layer sparse approximations - Analyzing the Approximation Error of the Fast Graph Fourier Transform - Flexible Multi-layer Sparse Approximations of Matrices and Applications - Are There Approximate Fast Fourier Transforms On Graphs? - Efficient matrices for signal processing and machine learning - FAμST: speeding up linear transforms for tractable inverse problems - Chasing butterflies: In search of efficient dictionaries - Multi-layer Sparse Matrix Factorization

- URL: http://faust.inria.fr/

6.2. SPADE

Sparse Audio Declipper

KEYWORDS: Audio - Sparse regularization - Declipping

SCIENTIFIC DESCRIPTION: SPADE (the Sparse Audio Declipper) allows to reproduce audio declipping experiments from the papers:

- Srdan Kitic, Nancy Bertin, Remi Gribonval. Audio Declipping by Cosparse Hard Thresholding. iTwist - 2nd international - Traveling Workshop on Interactions between Sparse models and Technology, Aug 2014, Namur, Belgium.

- Srdan Kitic, Nancy Bertin, Remi Gribonval. Sparsity and cosparsity for audio declipping: a flexible non-convex approach. LVA/ICA 2015 - The 12th International Conference on Latent Variable Analysis and Signal Separation, Aug 2015, Liberec, Czech Republic.

FUNCTIONAL DESCRIPTION: SPADE is a declipping algorithm developed by the PANAMA project-team. To the best of our knowledge SPADE achieves state-of-the-art audio declipping quality. Real-time processing of audio streams is possible.

The web site http://spade.inria.fr provides example audio files and allows users to test SPADE on their own files, either by downloading Matlab routines or using Inria's software demonstration platform, A∥go, to test it on the web.

NEWS OF THE YEAR: In 2018, the code has been robustified with the help of InriaTech for a potential industrial transfer. – In 2017, a web interface to demonstrate the potential of SPADE has been setup using the A∥go platform.

- Participants: Nancy Bertin, Clement Gaultier, Ewen Camberlein, Romain Lebarbenchon, Alexandre Sanchez, Rémi Gribonval and Srdan Kitic
- Contact: Rémi Gribonval
- Publications: Audio Declipping by Cosparse Hard Thresholding - Sparsity and cosparsity for audio declipping: a flexible non-convex approach
- URL: http://spade.inria.fr/

6.3. FASST

Flexible Audio Source Separation Toolbox
KEYWORD: Audio signal processing
SCIENTIFIC DESCRIPTION: FASST is a Flexible Audio Source Separation Toolbox, designed to speed up the conception and automate the implementation of new model-based audio source separation algorithms.

FASST 1.0 development was achieved by the METISS team in Rennes and is now deprecated.

FASST 2.1 development was jointly achieved by the PAROLE team in Nancy and the (former) TEXMEX team in Rennes through an Inria funded ADT (Action de Développement Technologique). PANAMA contributed to the development by coordinating and performing user tests, and to the dissemination in a Show-and-Tell ICASSP poster [58]. While the first implementation was in Matlab, the new implementation is in C++ (for core functions), with Matlab and Python user scripts. Version 2, including speedup and new features was released in 2014 and can be downloaded from http://bass-db.gforge.inria.fr/fasst/ .

Version 2.2.2 (current version) has been released in May 2018. This version was developed in the PANAMA team through the Inria funded ADT "FFWD" (FASST For Wider Dissemination). A version 3.0 is currently under development and will be released in 2019.

FUNCTIONAL DESCRIPTION: FASST is a Flexible Audio Source Separation Toolbox designed to speed up the conception and automate the implementation of new model-based audio source separation algorithms. It is the only audio source separation software available to the public (QPL licence) which simultaneously exploits spatial and spectral cues on the sources to separate.

NEWS OF THE YEAR: Version 2.2.2 (current version) has been released in May 2018. This version was developed in the PANAMA team through the Inria funded ADT FFWD (FASST For Wider Dissemination). A version 3.0 is currently under development and will be released in 2019.

- Participants: Alexey Ozerov, Nancy Bertin, Ewen Camberlein, Romain Lebarbenchon, Emmanuel Vincent, Frédéric Bimbot and Yann Salaun
- Contact: Emmanuel Vincent
- URL: http://bass-db.gforge.inria.fr/fasst/

6.4. Multi-channel BSS Locate Basic

KEYWORDS: Audio - Localization - Signal processing - Multichannel signal
SCIENTIFIC DESCRIPTION: Multi-Channel BSS Locate is a Matlab toolbox to estimate Direction Of Arrival (expressed both in azimuth and elevation) of multiple sources in a multi-channel audio signal recorded by an array of microphones. This toolbox implements the previous 8 angular spectrum methods presented in BSS Locate (GCC-PHAT, GCC-NONLIN, MUSIC and several SNR-based spectra).

NEWS OF THE YEAR: In 2018, with the help of InriaTech, selected parts of Multi-channel BSS Locate were ported to C++ in the perspective of a transfer

- Authors: Charles Blandin, Ewen Camberlein, Romain Lebarbenchon, Emmanuel Vincent, Alexey Ozerov and Nancy Bertin
- Contact: Emmanuel Vincent
- URL: http://bass-db.gforge.inria.fr/bss_locate/

6.5. VoiceHome-2

KEYWORDS: Speech processing - Audio signal processing - Source Separation - Source localization
SCIENTIFIC DESCRIPTION: New, extended version of the voiceHome corpus for distant-microphone speech processing in domestic environments. This 5-hour corpus includes short reverberated, noisy utterances (smart home commands) spoken in French by 12 native French talkers in diverse realistic acoustic conditions and recorded by an 8-microphone device at various angles and distances and in various noise conditions. Noise-only segments before and after each utterance are included in the recordings. Clean speech and spontaneous speech recorded in 12 real rooms distributed in 4 different homes are also available. All data have been fully annotated.

- Participants: Nancy Bertin, Ewen Camberlein, Romain Lebarbenchon, Emmanuel Vincent, Sunit Sivasankaran, Irina Illina and Frédéric Bimbot
- Contact: Nancy Bertin
- Publication: VoiceHome-2, an extended corpus for multichannel speech processing in real homes

SEMAGRAMME Project-Team

5. New Software and Platforms

5.1. ACGtk

Abstract Categorial Grammar Development Toolkit

KEYWORDS: Natural language processing - NLP - Syntactic analysis - Semantics

SCIENTIFIC DESCRIPTION: Abstract Categorial Grammars (ACG) are a grammatical formalism in which grammars are based on typed lambda-calculus. A grammar generates languages: the abstract language (the language of parse structures), and the object language (the language of the surface forms, e.g., strings, or higher-order logical formulas), which is the realization of the abstract language.

ACGtk provides two softwares to develop and to use ACGs: acgc, which is a grammar compiler, and acg, which is an interpreter of a command language that allows us, for instance, to parse and realize terms.

FUNCTIONAL DESCRIPTION: ACGtk provides softwares for developing and using Abstract Categorial Grammars (ACG).

NEWS OF THE YEAR: The new version extends the syntax for defining operators that can be used in grammars and removes dependencies to obsolete libraries. It also introduces some light optimizations compared to the previous one.

- Participants: Philippe De Groote, Jiri Marsik, Sylvain Pogodalla and Sylvain Salvati

- Contact: Sylvain Pogodalla

- Publications: A syntax-semantics interface for Tree-Adjoining Grammars through Abstract Categorial Grammars - ACGTK: un outil de développement et de test pour les grammaires catégorielles abstraites - Discourse Modeling with Abstract Categorial Grammars - On the expressive power of Abstract Categorial Grammars: Representing context-free formalisms - Towards abstract categorial grammars

- URL: http://acg.loria.fr/

5.2. Dep2pict

KEYWORDS: Syntactic analysis - Semantics

FUNCTIONAL DESCRIPTION: Dep2pict is a program for drawing graphical representation of dependency structures of natural language sentences. Dep2pict takes into account the modified format mixing surface and deep syntactic information used in deep-sequoia.

NEWS OF THE YEAR: The software was adapted to some extensions of the CoNLL format. A new Graphical User Interface (based on PyQt5) was built to replaced the previous one (https://gitlab.inria.fr/dep2pict/gui). It can be installed through PyPI (https://pypi.org/project/dep2pict-gui/)

- Contact: Bruno Guillaume

- URL: http://dep2pict.loria.fr/

5.3. Grew

Graph Rewriting

KEYWORDS: Semantics - Syntactic analysis - Natural language processing - Graph rewriting

FUNCTIONAL DESCRIPTION: Grew is a Graph Rewriting tool dedicated to applications in NLP. Grew takes into account confluent and non-confluent graph rewriting and it includes several mechanisms that help to use graph rewriting in the context of NLP applications (built-in notion of feature structures, parametrization of rules with lexical information).

NEWS OF THE YEAR: In 2018, the version 1.0 of Grew was released. The major novelties are a new implementation of lexical rules and the introduction of a Python binding (described in the book: Application of Graph Rewriting to Natural Language Processing)

- Participants: Bruno Guillaume, Guy Perrier and Guillaume Bonfante
- Contact: Bruno Guillaume
- Publications: Application de la réécriture de graphes au traitement automatique des langues - Application of Graph Rewriting to Natural Language Processing
- URL: http://grew.fr/

5.4. ZombiLingo

KEYWORDS: Syntactic analysis - Natural language processing - Lexical resource - Collaborative science

FUNCTIONAL DESCRIPTION: ZombiLingo is a prototype of a GWAP (Game With A Purpose) where gamers have to give linguistic information about the syntax of natural language sentence, currently in French, and later to other languages.

NEWS OF THE YEAR: The code was factorized and 3 independant librairies where built (available in the github project: https://github.com/gwaps4nlp/ to facilitate their usage in other projects.

- Authors: Bruno Guillaume, Karën Fort, Nicolas Lefebvre and Valentin Stern
- Contact: Karën Fort
- URL: http://zombilingo.org/

AUCTUS Team

6. New Software and Platforms

6.1. HuMoSoft

Human Motion Analysis Software

KEYWORDS: Movement analysis - 3D movement

FUNCTIONAL DESCRIPTION: HuMoSoft is based on the ROS platform. The acquisition data can come from different depth sensors, for example Kinect, via the Nuitrack JDK. An extended Kalman filter has been implemented, and motion analysis uses the RULA method.

- Authors: Jessica Colombel and David Daney
- Contact: Sylvain Pion
- URL: https://gitlab.inria.fr/auctus/kombos-server

<p align="center" style="color:red">Chroma Project-Team</p>

6. New Software and Platforms

6.1. kinetics

FUNCTIONAL DESCRIPTION: Software computing decision support strategies and decision-making

- Contact: Jilles Dibangoye

6.2. VI-SFM

FUNCTIONAL DESCRIPTION: Experimentary the closed Form Solution for usual-initial data fusion agains real and simulated fusion

- Authors: Agostino Martinelli and Jacques Kaiser
- Contact: Agostino Martinelli

6.3. Ground Elevation and Occupancy Grid Estimator (GEOG - Estimator)

KEYWORDS: Robotics - Environment perception

FUNCTIONAL DESCRIPTION: GEOG-Estimator is a system of joint estimation of the shape of the ground, in the form of a Bayesian network of constrained elevation nodes, and the ground-obstacle classification of a pointcloud. Starting from an unclassified 3D pointcloud, it consists of a set of expectation-maximization methods computed in parallel on the network of elevation nodes, integrating the constraints of spatial continuity as well as the influence of 3D points, classified as ground-based or obstacles. Once the ground model is generated, the system can then construct a occupation grid, taking into account the classification of 3D points, and the actual height of these impacts. Mainly used with lidars (Velodyne64, Quanergy M8, IBEO Lux), the approach can be generalized to any type of sensor providing 3D pointclouds. On the other hand, in the case of lidars, free space information between the source and the 3D point can be integrated into the construction of the grid, as well as the height at which the laser passes through the area (taking into account the height of the laser in the sensor model). The areas of application of the system spread across all areas of mobile robotics, it is particularly suitable for unknown environments. GEOG-Estimator was originally developed to allow optimal integration of 3D sensors in systems using 2D occupancy grids, taking into account the orientation of sensors, and indefinite forms of grounds. The ground model generated can be used directly, whether for mapping or as a pre-calculation step for methods of obstacle recognition or classification. Designed to be effective (real-time) in the context of embedded applications, the entire system is implemented on Nvidia graphics card (in Cuda), and optimized for Tegra X2 embedded boards. To ease interconnections with the sensor outputs and other perception modules, the system is implemented using ROS (Robot Operating System), a set of opensource tools for robotics.

- Authors: Amaury Nègre, Lukas Rummelhard, Lukas Rummelhard, Jean-Alix David and Christian Laugier
- Contact: Christian Laugier

6.4. CMCDOT

KEYWORDS: Robotics - Environment perception

FUNCTIONAL DESCRIPTION: CMCDOT is a Bayesian filtering system for dynamic occupation grids, allowing parallel estimation of occupation probabilities for each cell of a grid, inference of velocities, prediction of the risk of collision and association of cells belonging to the same dynamic object. Last generation of a suite of Bayesian filtering methods developed in the Inria eMotion team, then in the Inria Chroma team (BOF, HSBOF, ...), it integrates the managment of hybrid sampling methods (classical occupancy grids for static parts, particle sets for parts dynamics) into a Bayesian unified programming formalism , while incorporating elements resembling the Dempster-Shafer theory (state "unknown", allowing a focus of computing resources). It also offers a projection system of the estimated scene in the near future, to reference potential collisions with the ego-vehicle or any other element of the environment, as well as very low cost pre-segmentation of coherent dynamic spaces (taking into account speeds). It takes as input instantaneous occupation grids generated by sensor models for different sources, the system is composed of a ROS package, to manage the connectivity of I / O, which encapsulates the core of the embedded and optimized application on GPU Nvidia (Cuda), allowing real-time analysis of the direct environment on embedded boards (Tegra X1, X2). ROS (Robot Operating System) is a set of open source tools to develop software for robotics. Developed in an automotive setting, these techniques can be exploited in all areas of mobile robotics, and are particularly suited to highly dynamic and uncertain environment management (eg urban scenario, with pedestrians, cyclists, cars, buses, etc.).

- Authors: Amaury Nègre, Lukas Rummelhard, Jean-Alix David and Christian Laugier
- Partners: CEA - CNRS
- Contact: Christian Laugier

6.5. cuda_grid_fusion

KEYWORDS: Robotics - Environment perception
FUNCTIONAL DESCRIPTION: This module, directly implemented in ROS / Cuda, performs the merge of occupancy grids, defined in the format proposed in CMCDOT (probabilities integrating the "visibility" information of the cell, via the coefficients "unknown") thanks to an original method, allowing not only consistency with the rest of the system, but also a nuanced consideration of confidence criteria towards the various sources of information.

- Authors: Lukas Rummelhard and Jean-Alix David
- Contact: Lukas Rummelhard

6.6. cuda_laser_grid

KEYWORDS: Robotics - Environment perception
FUNCTIONAL DESCRIPTION: This module generates occupation grids from "almost" planar lidar. The sensor model, as well as the outputs, have been modified, in order to be fully consistent with the CMCDOT and grid fusion module formats.

- Authors: Amaury Nègre, Lukas Rummelhard and Jean-Alix David
- Contact: Lukas Rummelhard

6.7. CMCDOT-Tools

KEYWORD: Robotics
FUNCTIONAL DESCRIPTION: Tools for CMCDOT Software

- Authors: Amaury Nègre, Lukas Rummelhard, Jean-Alix David, Mathias Perrollaz, Procopio Silveira-Stein, Jérôme Lussereau and Nicolas Vignard
- Contact: Jean-Alix David

6.8. DWA Planner on occupancy grid

Dynamic Window Approach Planner based on occupancy grid

KEYWORD: Navigation

FUNCTIONAL DESCRIPTION: This program considers : - a given target - an occupancy grid which represents the environment - the odometry of the vehicle With these data, it computes the commands for a safe navigation towards the target.

- Authors: Christian Laugier and Thomas Genevois
- Partner: CEA
- Contact: Christian Laugier

6.9. Zoe Simulation

Simulation of Inria's Renault Zoe in Gazebo environment

KEYWORD: Simulation

FUNCTIONAL DESCRIPTION: This simulation represents the Renault Zoe vehicle considering the realistic physical phenomena (friction, sliding, inertia, ...). The simulated vehicle embeds sensors similar to the ones of the actual vehicle. They provide measurement data under the same format. Moreover the software input/output are identical to the vehicle's. Therefoe any program executed on the vehicle can be used with the simulation and reciprocally.

- Authors: Christian Laugier, Nicolas Turro and Thomas Genevois
- Contact: Christian Laugier

6.10. PedSim-ROS

FUNCTIONAL DESCRIPTION: Simulation of moving people and mobile robots that can detect agents around them. Integration of ROS mobile robots with the PedSim simulator.

- Contact: Jacques Saraydaryan

6.11. EKF Odom

EKF based localisation for vehicles

KEYWORDS: Localization - Autonomous Cars

FUNCTIONAL DESCRIPTION: This software fuses IMU data with wheel rotation or speed measurement inside an Extended Kalman Filter. It estimates the state position, orientation, speed, angular speed, acceleration.

- Authors: Thomas Genevois and Christian Laugier
- Contact: Christian Laugier
- URL: https://team.inria.fr/chroma/en/

6.12. Light Vehicle Simulation

Simulation of a light vehicle in Gazebo environment

KEYWORD: Simulation

FUNCTIONAL DESCRIPTION: This simulation represents a light vehicle considering the realistic physical phenomena (friction, sliding, inertia, ...). The simulated vehicle embeds sensors similar to the ones of the actual vehicle. They provide measurement data under the same format. Moreover the software input/output are identical to the vehicle's. Therefore any program executed on the vehicle can be used with the simulation and reciprocally.

- Authors: Thomas Genevois and Christian Laugier
- Contact: Christian Laugier
- URL: https://team.inria.fr/chroma/en/

6.13. CarHybridSim

Hybrid simulation for autonomous cars with high traffic

KEYWORDS: Simulation - Autonomous Cars

FUNCTIONAL DESCRIPTION: Open source tool for simulating autonomous vehicles in complex, high traffic, scenarios. The hybrid simulation fully integrates and synchronizes a microscopic, multi-modal traffic simulator and a complex 3D simulator.

- Contact: Mario Garzon Oviedo
- URL: https://github.com/marioney/hybrid_simulation

6.14. SimuDronesGR

Simultion of UAV fleets with Gazebo/ROS

KEYWORDS: Robotics - Simulation

FUNCTIONAL DESCRIPTION: The simulator includes the following functionality : 1) Simulation of the mechanical behavior of an Unmanned Aerial Vehicle : * Modeling of the body's aerodynamics with lift, drag and moment * Modeling of rotors' aerodynamics using the forces and moments' expressions from Philppe Martin's and Erwan Salaün's 2010 IEEE Conference on Robotics and Automation paper "The True Role of Accelerometer Feedback in Quadrotor Control". 2) Gives groundtruth informations : * Positions in East-North-Up reference frame * Linear velocity in East-North-Up and Front-Left-Up reference frames * Linear acceleration in East-North-Up and Front-Left-Up reference frames * Orientation from East-North-Up reference frame to Front-Left-Up reference frame (Quaternions) * Angular velocity of Front-Left-Up reference frame expressed in Front-Left-Up reference frame. 3) Simulation of the following sensors : * Inertial Measurement Unit with 9DoF (Accelerometer + Gyroscope + Orientation) * Barometer using an ISA model for the troposphere (valid up to 11km above Mean Sea Level) * Magnetometer with the earth magnetic field declination * GPS Antenna with a geodesic map projection.

RELEASE FUNCTIONAL DESCRIPTION: Initial version

- Author: Vincent Le Doze
- Partner: Insa de Lyon
- Contact: Vincent Le Doze

<h1 style="text-align:center; color:red;">DEFROST Project-Team</h1>

6. New Software and Platforms

6.1. SOFA

Simulation Open Framework Architecture

KEYWORDS: Real time - Multi-physics simulation - Medical applications

FUNCTIONAL DESCRIPTION: SOFA is an Open Source framework primarily targeted at real-time simulation, with an emphasis on medical simulation. It is mostly intended for the research community to help develop new algorithms, but can also be used as an efficient prototyping tool. Based on an advanced software architecture, it allows : the creation of complex and evolving simulations by combining new algorithms with algorithms already included in SOFA, the modification of most parameters of the simulation (deformable behavior, surface representation, solver, constraints, collision algorithm, etc.) by simply editing an XML file, the building of complex models from simpler ones using a scene-graph description, the efficient simulation of the dynamics of interacting objects using abstract equation solvers, the reuse and easy comparison of a variety of available methods.

- Participants: Christian Duriez, François Faure, Hervé Delingette and Stéphane Cotin
- Partner: IGG
- Contact: Stéphane Cotin
- URL: http://www.sofa-framework.org

6.2. SoftRobots

SoftRobots plugin for Sofa

KEYWORDS: Numerical simulations - Problem inverse - Soft robotics

FUNCTIONAL DESCRIPTION: This plugin allows the modeling of deformable robots in the Sofa platform. It allows the modeling of different actuators, such as cable, pneumatic pressure, hydraulics and other simpler types of actuation. It also contains useful tools for animation design or communication with the robot. Coupled with the SoftRobots.Inverse plugin, it also allows the control of these robots. More information can be found on the dedicated website https://project.inria.fr/softrobot/.

- Participants: Christian Duriez, Olivier Goury, Jérémie Dequidt, Damien Marchal, Eulalie Coevoet, Erwan Douaille and Félix Vanneste
- Contact: Christian Duriez
- URL: https://project.inria.fr/softrobot/

6.3. Model Order Reduction Plugin for SOFA

KEYWORDS: Model Order Reduction - Sofa - Finite element modelling

SCIENTIFIC DESCRIPTION: This plugin allows speed-up of SOFA simulations by providing tools to create a reduced version of the SOFA simulation that runs at much higher rates but remains accurate. Starting with a snapshot of the object deformations on a high-dimensional Finite Element mesh, Proper Orthogonal Decomposition (POD) is used to compute a reduced basis of small dimension representing correctly all the possible deformations of the object. The original system describing the object motion is then greatly reduced. To keep numerical efficiency, a hyper-reduction method is used to speed-up the construction of the reduced system.

FUNCTIONAL DESCRIPTION: This plugin allows to dramatically reduce computational time in mechanical simulation in the SOFA framework. A reduced simulation, of much smaller dimension but still accurate is created in an automatic way by the plugin. Building the reduced model may take time, but this operation is made once only. The user can then benefit from a reduced and interactive version of his/her simulation without significant loss of accuracy.

RELEASE FUNCTIONAL DESCRIPTION: This is the first version of the plugin.

NEWS OF THE YEAR: Publication using this plugin accepted dans IEEE Transactions on Robotics

- Participants: Olivier Goury, Félix Vanneste, Christian Duriez and Eulalie Coevoet

- Contact: Olivier Goury

- Publication: Fast, generic and reliable control and simulation of soft robots using model order reduction

- URL: https://project.inria.fr/modelorderreduction/

6.4. SoftRobots.Inverse

KEYWORDS: Sofa - SoftRobots

FUNCTIONAL DESCRIPTION: This plugin builds on the plugin SoftRobots (https://project.inria.fr/softrobot/). Inside the plugin, there is some constraint components that are used to describe the robot (effectors, actuators, sensors). An optimisation algorithm is provided to find the efforts to put on actuators in order to place the robot in a the closest possible configuration than the one described by "effectors", or to a state described by "sensors". This method used to control the soft-robots in the task space is patented.

- Partners: CNRS - Université de Lille - Ecole Centrale de Lille

- Contact: Christian Duriez

- URL: https://project.inria.fr/softrobot.inverse

<p style="text-align:center">**FLOWERS Project-Team**</p>

6. New Software and Platforms

6.1. 3rd hand infrastructure

KEYWORDS: Interaction - Robotics - Infrastructure software - Framework - Robot Operating System (ROS)
FUNCTIONAL DESCRIPTION: The infrastructure is predicate-based to handle relational actions and covers perception (scene description generation, human actions recognition), decision making (teleoperated, scripted or learning from demonstrations), interaction with end users (GUI, voice, gestures) and parallel executions of robotic actions (hold, pick, grasp, bring, ...).

- Contact: Yoan Mollard
- URL: https://github.com/3rdHand-project/thr_infrastructure

6.2. Aversive++

FUNCTIONAL DESCRIPTION: Aversive++ is a C++ library that eases micro-controller programming. Its aim is to provide an interface simple enough to be able to create complex applications, and optimized enough to enable small micro-controllers to execute these applications. The other aspect of this library is to be multiplatform. Indeed, it is designed to provide the same API for a simulator (named SASIAE) and for AVR-based and ARM-based micro-controllers.

- Contact: Loïc Dauphin
- URL: https://github.com/AversivePlusPlus

6.3. DMP-BBO

Black-Box Optimization for Dynamic Movement Primitives
KEYWORD: -
FUNCTIONAL DESCRIPTION: The DMP-BBO Matlab library is a direct consequence of the insight that black-box optimization outperforms reinforcement learning when using policies represented as Dynamic Movement Primitives. It implements several variants of the PIBB algorithm for direct policy search. The dmp-bbo C++ library has been extended to include the "unified model for regression". The implementation of several of the function approximators have been made real-time compatible.

- Participant: Freek Stulp
- Partner: ENSTA
- Contact: Freek Stulp
- URL: https://github.com/stulp/dmpbbo

6.4. Explauto

an autonomous exploration library
KEYWORD: Exploration

SCIENTIFIC DESCRIPTION: An important challenge in developmental robotics is how robots can be intrinsically motivated to learn efficiently parametrized policies to solve parametrized multi-task reinforcement learning problems, i.e. learn the mappings between the actions and the problem they solve, or sensory effects they produce. This can be a robot learning how arm movements make physical objects move, or how movements of a virtual vocal tract modulates vocalization sounds. The way the robot will collects its own sensorimotor experience have a strong impact on learning efficiency because for most robotic systems the involved spaces are high dimensional, the mapping between them is non-linear and redundant, and there is limited time allowed for learning. If robots explore the world in an unorganized manner, e.g. randomly, learning algorithms will be often ineffective because very sparse data points will be collected. Data are precious due to the high dimensionality and the limited time, whereas data are not equally useful due to non-linearity and redundancy. This is why learning has to be guided using efficient exploration strategies, allowing the robot to actively drive its own interaction with the environment in order to gather maximally informative data to optimize the parametrized policies. In the recent year, work in developmental learning has explored various families of algorithmic principles which allow the efficient guiding of learning and exploration.

Explauto is a framework developed to study, model and simulate curiosity-driven learning and exploration in real and simulated robotic agents. Explauto's scientific roots trace back from Intelligent Adaptive Curiosity algorithmic architecture [122], which has been extended to a more general family of autonomous exploration architectures by [1] and recently expressed as a compact and unified formalism [113]. The library is detailed in [114]. In Explauto, interest models are implementing the strategies of active selection of particular problems / goals in a parametrized multi-task reinforcement learning setup to efficiently learn parametrized policies. The agent can have different available strategies, parametrized problems, models, sources of information, or learning mechanisms (for instance imitate by mimicking vs by emulation, or asking help to one teacher or to another), and chooses between them in order to optimize learning (a processus called strategic learning [118]). Given a set of parametrized problems, a particular exploration strategy is to randomly draw goals/ RL problems to solve in the motor or problem space. More efficient strategies are based on the active choice of learning experiments that maximize learning progress using bandit algorithms, e.g. maximizing improvement of predictions or of competences to solve RL problems [122]. This automatically drives the system to explore and learn first easy skills, and then explore skills of progressively increasing complexity. Both random and learning progress strategies can act either on the motor or on the problem space, resulting in motor babbling or goal babbling strategies.

- Motor babbling consists in sampling commands in the motor space according to a given strategy (random or learning progress), predicting the expected effect, executing the command through the environment and observing the actual effect. Both the parametrized policies and interest models are finally updated according to this experience.

- Goal babbling consists in sampling goals in the problem space and to use the current policies to infer a motor action supposed to solve the problem (inverse prediction). The robot/agent then executes the command through the environment and observes the actual effect. Both the parametrized policies and interest models are finally updated according to this experience.It has been shown that this second strategy allows a progressive solving of problems much more uniformly in the problem space than with a motor babbling strategy, where the agent samples directly in the motor space [1].

FUNCTIONAL DESCRIPTION: This library provides high-level API for an easy definition of:
- Real and simulated robotic setups (Environment level),
- Incremental learning of parametrized policies (Sensorimotor level),
- Active selection of parametrized RL problems (Interest level).

The library comes with several built-in environments. Two of them corresponds to simulated environments: a multi-DoF arm acting on a 2D plan, and an under-actuated torque-controlled pendulum. The third one allows to control real robots based on Dynamixel actuators using the Pypot library. Learning parametrized policies involves machine learning algorithms, which are typically regression algorithms to learn forward models,
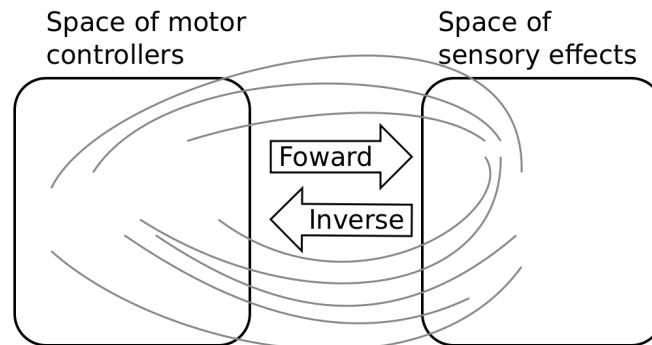
Figure 1. Complex parametrized policies involve high dimensional action and effect spaces. For the sake of visualization, the motor M and sensory S spaces are only 2D each in this example. The relationship between M and S is non-linear, dividing the sensorimotor space into regions of unequal stability: small regions of S can be reached very precisely by large regions of M, or large regions in S can be very sensitive to variations in M.: s as well as a non-linear and redundant relationship. This non-linearity can imply redundancy, where the same sensory effect can be attained using distinct regions in M.

from motor controllers to sensory effects, and optimization algorithms to learn inverse models, from sensory effects, or problems, to the motor programs allowing to reach them. We call these sensorimotor learning algorithms sensorimotor models. The library comes with several built-in sensorimotor models: simple nearest-neighbor look-up, non-parametric models combining classical regressions and optimization algorithms, online mixtures of Gaussians, and discrete Lidstone distributions. Explauto sensorimotor models are online learning algorithms, i.e. they are trained iteratively during the interaction of the robot in theenvironment in which it evolves. Explauto provides also a unified interface to define exploration strategies using the InterestModel class. The library comes with two built-in interest models: random sampling as well as sampling maximizing the learning progress in forward or inverse predictions.

Explauto environments now handle actions depending on a current context, as for instance in an environment where a robotic arm is trying to catch a ball: the arm trajectories will depend on the current position of the ball (context). Also, if the dynamic of the environment is changing over time, a new sensorimotor model (Non-Stationary Nearest Neighbor) is able to cope with those changes by taking more into account recent experiences. Those new features are explained in Jupyter notebooks.

This library has been used in many experiments including:

- the control of a 2D simulated arm,
- the exploration of the inverse kinematics of a poppy humanoid (both on the real robot and on the simulated version),
- acoustic model of a vocal tract.

Explauto is crossed-platform and has been tested on Linux, Windows and Mac OS. It has been released under the GPLv3 license.

- Contact: Sébastien Forestier
- URL: https://github.com/flowersteam/explauto

6.5. HiPi Board

FUNCTIONAL DESCRIPTION: Hipi is a board to control robots on Raspberry Pi. It is an extension of the Pixl board with the following features:

- A DC/DC power converter from 12V (motor) to 5V (Raspberry Pi) at 3A.
- A stereo audio amplifier 3W.
- A MPU9250 central motion unit .
- A RS232 and a RS485 bus connected to the Raspberry Pi by SPI for driving MX and RX Dynamixel motor series.

This board will be integrated soon in the new head of the Poppy Humanoid and Poppy Torso.

Using the Raspberry Pi for every Poppy robots will simplify the hardware complexity (we maintain 4 types of embedded boards, with different Linux kernel and configurations) and improve the usage and installation of new robots.

- Contact: Theo Segonds
- URL: https://forum.poppy-project.org/t/poppy-1-1-hipi/2137

6.6. IKPy

Inverse Kinematics Python Library
FUNCTIONAL DESCRIPTION: IKPy is a Python Inverse Kinematics library, designed to be simple to use and extend. It provides Forward and Inverse kinematics functionality, bundled with helper tools such as 3D plotting of the kinematics chains. Being written entirely in Python, IKPy is lightweight and is based on numpy and scipy for fast optimization. IKPy is compatible with many robots, by automatically parsing URDF files. It also supports other (such as DH-parameters) and custom representations. Moreover, it provides a framework to easily implement new Inverse Kinematics strategies. Originally developed for the Poppy project, it can also be used as a standalone library.

- Contact: Pierre Manceron
- URL: https://github.com/Phylliade/ikpy

6.7. KERAS-QR

KERAS with Quick Reset
KEYWORDS: Library - Deep learning

- Participant: Florian Golemo
- Contact: Florian Golemo
- URL: https://github.com/fgolemo/keras

6.8. KidBreath

FUNCTIONAL DESCRIPTION: KidBreath is a web responsive application composed by several interactive contents linked to asthma and displayed to different forms: learning activities with quiz, short games and videos. There are profil creation and personalization, and a part which describes historic and scoring of learning activities, to see evolution of Kidreath use. To test Kidlearn algorithm, it is iadapted and integrated on this platform. Development in PHP, HTML-5, CSS, MySQL, JQuery, Javascript. Hosting in APACHE, LINUX, PHP 5.5, MySQL, OVH.

- Partner: ItWell SAS
- Contact: Alexandra Delmas
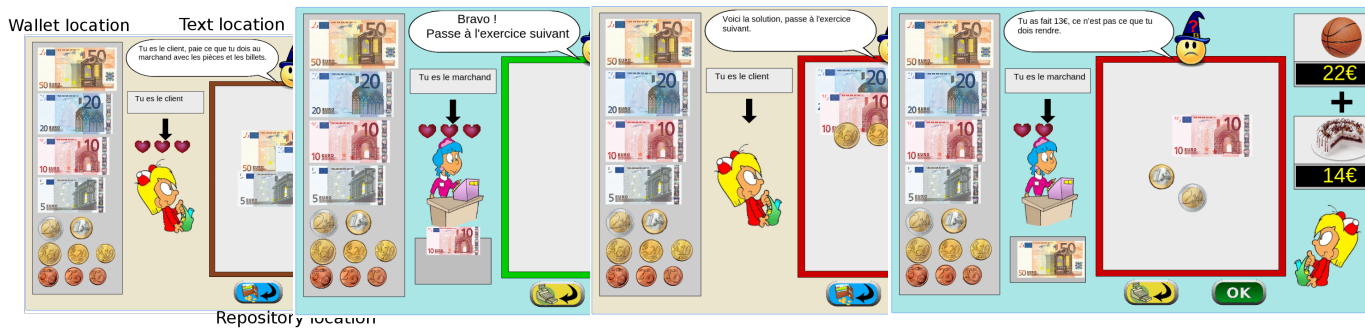- URL: http://www.kidbreath.fr

Figure 2. Four principal regions are defined in the graphical interface. The first is the wallet location where users can pick and drag the money items and drop them on the repository location to compose the correct price. The object and the price are present in the object location. Four different types of exercises exist: M : customer/one object, R : merchant/one object, MM : customer/two objects, RM : merchant/two objects.

6.9. Kidlearn: money game application

FUNCTIONAL DESCRIPTION: The games is instantiated in a browser environment where students are proposed exercises in the form of money/token games (see Figure 2). For an exercise type, one object is presented with a given tagged price and the learner has to choose which combination of bank notes, coins or abstract tokens need to be taken from the wallet to buy the object, with various constraints depending on exercises parameters. The games have been developed using web technologies, HTML5, javascript and Django.

- Contact: Benjamin Clement
- URL: https://flowers.inria.fr/research/kidlearn/

6.10. Kidlearn: script for Kidbreath use

FUNCTIONAL DESCRIPTION: A new way to test Kidlearn algorithms is to use them on Kidbreath Plateform. The Kidbreath Plateform use apache/PHP server, so to facilitate the integration of our algorithm, a python script have been made to allow PHP code to use easily the python library already made which include our algorithms.

Github link to explanation about it : https://github.com/flowersteam/kidlearn/.

- Contact: Benjamin Clement
- URL: https://github.com/flowersteam/kidlearn/

6.11. KidLearn

KEYWORD: Automatic Learning
FUNCTIONAL DESCRIPTION: KidLearn is a software which adaptively personalize sequences of learning activities to the particularities of each individual student. It aims at proposing to the student the right activity at the right time, maximizing concurrently his learning progress and its motivation.

- Participants: Benjamin Clement, Didier Roy, Manuel Lopes and Pierre Yves Oudeyer
- Contact: Pierre-Yves Oudeyer
- URL: https://flowers.inria.fr/research/kidlearn/

6.12. Kinect 2 Server

Kinect 2 server

KEYWORDS: Depth Perception - Speech recognition - Gesture recognition - Kinect

FUNCTIONAL DESCRIPTION: The server written in C# uses the Kinect SDK v2 to get the RGBD raw image, skeleton tracking information, recognized speech. It also uses the text-to-speech from Microsoft. Then it streams JSON data over the network using the Publisher/Subscriber pattern from the ZeroMQ network library. A Linux client has been written in Python but it can be written in any other language that is compatible with ZeroMQ. Features are controllable through a Graphical User Interface on Windows, or through the code from any Linux/Windows client. The clients can for instance enable features (speech recognition on, skeleton tracking off, . . .) and parameters (set new speech to recognize, change language, . . .) from remote.

- Contact: Yoan Mollard
- URL: https://github.com/baxter-flowers/kinect_2_server/

6.13. Multimodal

FUNCTIONAL DESCRIPTION: The python code provides a minimum set of tools and associated libraries to reproduce the experiments in [98] , together with the choreography datasets. The code is primarily intended for reproduction of the mulimodal learning experiment mentioned above. It has already been reused in several experimentations by other member of the team and is expected to play an important role in further collaborations. It is also expected that the public availability of the code encourages further experimentation by other scientists with data coming from other domains, thus increasing both the impact of the aforementioned publication and the knowledge on the algorithm behaviors.

- Participant: Olivier Mangin
- Contact: Olivier Mangin
- URL: https://github.com/omangin/multimodal

6.14. OptiTrack

FUNCTIONAL DESCRIPTION: This python library allows you to connect to an OptiTrack from NaturalPoint. This camera permits the tracking of 3D markers efficiently and robustly. With this library, you can connect to the Motive software used by the OptiTrack and retrieve the 3D position and orientation of all your tracked markers directly from python.

- Participant: Pierre Rouanet
- Contact: Pierre Rouanet
- URL: http://www.optitrack.com/

6.15. Pixl Board

FUNCTIONAL DESCRIPTION: Pixl is a tiny board used to create low cost robots based on Raspberry Pi board and Dynamixel XL-320 motors. This board has 2 main features:

- The power part, allowing the user to plug a 7.5V AC/DC converter or a battery directly into the Pixl. This power is distributed to all XL320 motors and is converted to 5V for the Raspberry Pi board.
- The communication part, which converts full duplex to half duplex and vice-versa. The half duplex part switch between RX and TX automatically. Another connector allows the user to connect his XL320 network.

The board is used in the Poppy Ergo Jr robot.

- Contact: Theo Segonds
- URL: https://github.com/poppy-project/pixl

6.16. Poppy

FUNCTIONAL DESCRIPTION: The Poppy Project team develops open-source 3D printed robots platforms based on robust, flexible, easy-to-use and reproduce hardware and software. In particular, the use of 3D printing and rapid prototyping technologies is a central aspect of this project, and makes it easy and fast not only to reproduce the platform, but also to explore morphological variants. Poppy targets three domains of use: science, education and art.

In the Poppy project we are working on the Poppy System which is a new modular and open-source robotic architecture. It is designed to help people create and build custom robots. It permits, in a similar approach as Lego, building robots or smart objects using standardized elements.

Poppy System is a unified system in which essential robotic components (actuators, sensors...) are independent modules connected with other modules through standardized interfaces:

- Unified mechanical interfaces, simplifying the assembly process and the design of 3D printable parts.
- Unified communication between elements using the same connector and bus for each module.
- Unified software, making it easy to program each module independently.

Our ambition is to create an ecosystem around this system so communities can develop custom modules, following the Poppy System standards, which can be compatible with all other Poppy robots.

- Participants: Jonathan Grizou, Matthieu Lapeyre, Pierre Rouanet and Pierre-Yves Oudeyer
- Contact: Pierre-Yves Oudeyer
- URL: https://www.poppy-project.org/

6.17. Poppy Ergo Jr

FUNCTIONAL DESCRIPTION: Poppy Ergo Jr is an open hardware robot developed by the Poppy Project to explore the use of robots in classrooms for learning robotic and computer science.

It is available as a 6 or 4 degrees of freedom arm designed to be both expressive and low-cost. This is achieved by the use of FDM 3D printing and low cost Robotis XL-320 actuators. A Raspberry Pi camera is attached to the robot so it can detect object, faces or QR codes.

The Ergo Jr is controlled by the Pypot library and runs on a Raspberry pi 2 or 3 board. Communication between the Raspberry Pi and the actuators is made possible by the Pixl board we have designed.

The Poppy Ergo Jr robot has several 3D printed tools extending its capabilities. There are currently the lampshade, the gripper and a pen holder.

With the release of a new Raspberry Pi board early 2016, the Poppy Ergo Jr disk image was updated to support Raspberry Pi 2 and 3 boards. The disk image can be used seamlessly with a board or the other.

- Contact: Theo Segonds
- URL: https://github.com/poppy-project/poppy-ergo-jr

6.18. Poppy Ergo Jr Installer

FUNCTIONAL DESCRIPTION: An alternative way to install the Ergo Jr robot software is made available using containers.

Users can own their own operating system installation, then add the Ergo Jr required software in a sandboxed environment. This results in a non-intrusive installation on the host system.

Docker containers implementation were used, and image is hosted at Docker Hub.
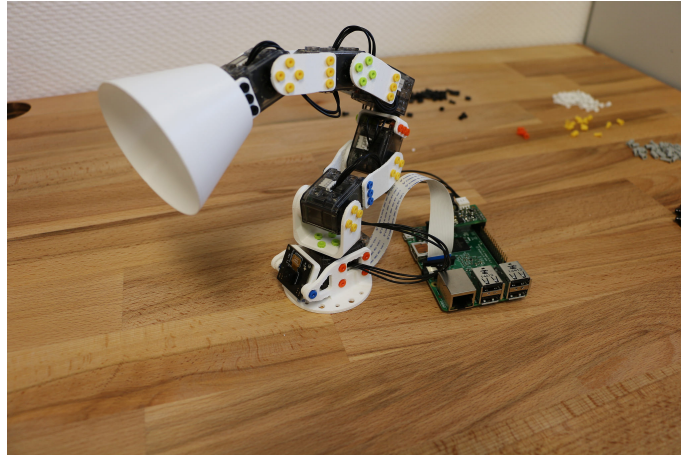
- Contact: Damien Caselli
- URL: https://hub.docker.com/r/poppycommunity/ergo-jr/

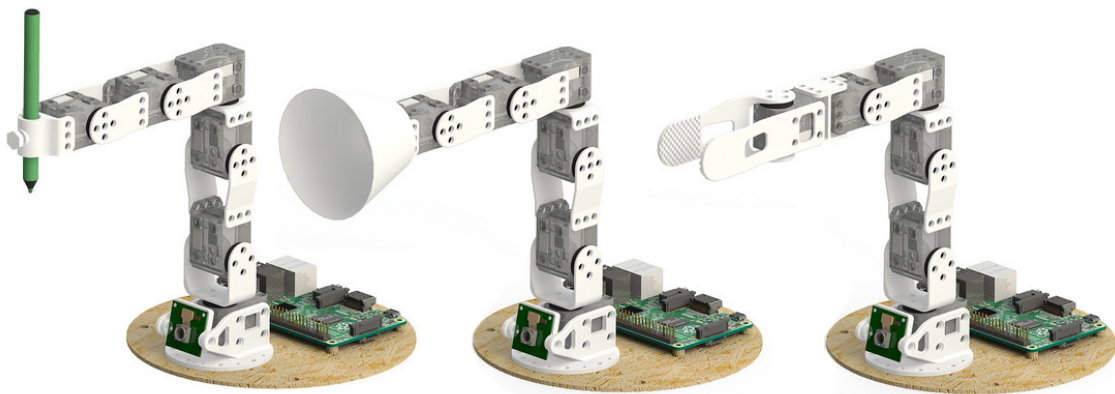*Figure 3. Poppy Ergo Jr, 6-DoFs arm robot for education*

Figure 4. The available Ergo Jr tools: a pen holder, a lampshade and a gripper

6.19. Poppy Ergo Jr Simulator

FUNCTIONAL DESCRIPTION: Poppy Project, through Poppy Education, wants users to get used to robotics, even without owning a physical robot.

For that purpose, Poppy Project team created a dummy robot in Pypot that is meant to be used in conjunction with a consumer application. We choose to develop a web hosted application using a 3D engine (Threejs) to render the robot.

Our ambition is to have a completely standalone simulated robot with physics. Some prototypes were created to benchmark possible solutions.

- Contact: Damien Caselli
- URL: https://github.com/poppy-project/poppy-simu

6.20. ProMP

Probabilistic Movement Primitives
KEYWORDS: Interaction - Robotics - Probability - Motion model - Robot Operating System (ROS)
FUNCTIONAL DESCRIPTION: Joint-space primitives with a task-space constraint: The primitives are stored in joint-space but demonstrations are provided both in joint space and task space, context. Thanks to this context, task-space goals can be requested to these joint-space primitives. The benefit is that requesting a new task-space goal does not require to call an IK method which would return demonstrations-agnostic joint configurations.

Vocal interactive learning and clustering: This work includes an interactive learning aspect which allows to automatically cluster motor primitives based on the standard deviation of their demonstrations. A new primitive is created automatically if the provided demonstration is out of 2 standard deviation of the existing primitives, otherwise the demonstration is distributed to an existing one.

- Contact: Yoan Mollard
- URL: https://github.com/baxter-flowers/promplib

6.21. PyPot

SCIENTIFIC DESCRIPTION: Pypot is a framework developed to make it easy and fast to control custom robots based on Dynamixel motors. This framework provides different levels of abstraction corresponding to different types of use. Pypot can be used to:

- control Robotis motors through a USB2serial device,
- define the structure of a custom robot and control it through high-level commands,
- define primitives and easily combine them to create complex behavior.

Pypot is part of the Poppy project. It is the core library used by the Poppy robots. This abstraction layer allows to seamlessly switch from a given Poppy robot to another. It also provides a common set of tools, such as forward and inverse kinematics, simple computer vision, recording and replaying moves, or easy access to the autonomous exploration library Explauto.

To extend pypot application domains and connection to outside world, it also provides an HTTP API. On top of providing an easy way to connect to smart sensors or connected devices, it is notably used to connect to Snap!, a variant of the well-known Scratch visual programming language.

FUNCTIONAL DESCRIPTION: Pypot is entirely written in Python to allow for fast development, easy deployment and quick scripting by non-expert developers. It can also benefit from the scientific and machine learning libraries existing in Python. The serial communication is handled through the standard library and offers high performance (10ms sensorimotor loop) for common Poppy uses. It is cross-platform and has been tested on Linux, Windows and Mac OS.

Figure 5. Example of using pypot to program a robot to reproduce a drawn shape

Pypot is also compatible with the V-REP simulator. This allows the transparent switch from a real robot to its simulated equivalent with a single code base.

Finally, it has been developed to be easily and quickly extended for other types of motors and sensors.

It works with Python 2.7 or Python 3.3 or later, and has also been adapted to the Raspberry Pi board.

Pypot has been connected to Snap!, a variant of the famous Scratch visual language, developed to teach computer science to children. It is based on a drag-and-drop blocks interface to write scripts by assembling those blocks.

Thanks to the Snap! HTTP block, a connection can be made to pypot allowing users to directly control robots through their visual interfaces. A set of dedicated Snap! blocks have been designed, such as *set motor position* or *get motor temperature*. Thanks to the Snap! HTTP block, users can control robots through this visual interfaces connecting to Pypot. A set of dedicated Snap! blocks has been designed, such as *set motor position* or *get motor temperature*.

Snap! is also used as a tool to program the robot by demonstration. Using the *record* and *play* blocks, users can easily trigger kinesthetic recording of the whole robot or only a specific subpart, such as an arm. These records can then be played or "mixed" - either played in sequence or simultaneously - with other recordings to compose complex choreographies. The moves are encoded as a model of mixture of gaussians (GMM) which allows the definition of clean mathematical operators for combining them.

This recording tool has been developed and used in collaboration with artists who show interest in the concept of robotic moves.

- Participants: Damien Caselli, Matthieu Lapeyre, Pierre Rouanet, Steve Nguyen and Theo Segonds
- Contact: Theo Segonds
- URL: https://github.com/poppy-project/pypot

6.22. PyQMC

Python library for Quasi-Metric Control
FUNCTIONAL DESCRIPTION: PyQMC is a python library implementing the control method described in http://dx.doi.org/10.1371/journal.pone.0083411 It allows to solve discrete markovian decision processes by computing a Quasi-Metric on the state space. This model based method has the advantage to be goal independant and thus can produce a policy for any goal with relatively few recomputation. New addition to this method is the possibility of online learning of the transition model and the Quasi-Metric.

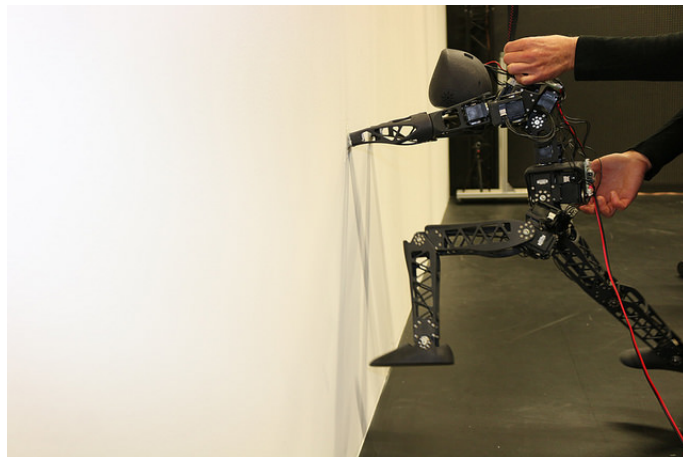*Figure 6. Using Snap! to program a robot by demonstration and create complex choreographies*

Figure 7. Artistic project exploring the concept of robotic move.

- Participant: Steve Nguyen
- Contact: Steve Nguyen
- URL: https://github.com/SteveNguyen/pyqmc

6.23. ROS Optitrack Publisher

KEYWORDS: Target tracking - Robot Operating System (ROS)

FUNCTIONAL DESCRIPTION: This package allows to publish optitrack markers declared as rigid bodies as TF transforms. Data is gathered through the embedded VRPN server of Motive/Arena. Only rigid bodies are requested to the server, thus single points in 2D/3D are ignored. VRPN server can be enable in View > Data streaming in Motive.

- Contact: Yoan Mollard
- URL: https://github.com/baxter-flowers/optitrack_publisher

6.24. ThifloNet

KEYWORDS: Deep learning - Policy Learning

SCIENTIFIC DESCRIPTION: We created a software architecture that combines a state-of-the-art computer vision system with a policy learning framework. This system is able to perceive a visual scene, given by a still image, extract facts ("predicates"), and propose an optimal action to achieve a given goal. Both systems are chained into a pipeline that is trained by presenting images and demonstrating an optimal action. By providing this information, both the predicate recognition model and the policy learning model are updated.

Our architecture is based on the recent works of Lerer, A., Gross, S., & Fergus, R., 2016 ("Learning Physical Intuition of Block Towers by Example"). They created a large network able to identify physical properties of stacked blocks. Analogously our vision system utilizes the same network layout (without the image prediction auxiliary output), with an added output layer for predicates, based on the expected number and arity of predicates. The vision subsystem is not trained with a common cross-entropy or MSE loss function, but instead receives its loss form the policy learning subsystem. The policy learning module calculates the loss as optimal combination of predicates for the given expert action.

By using this combination of systems, the architecture as a whole requires significantly fewer data samples than other systems (which exclusively utilize neural networks). This makes the approach more feasible to real-life applciation with actual live demonstration.

FUNCTIONAL DESCRIPTION: The neural network consists of ResNet-50 (the currently best-performing computer vision system), with 50 layers, 2 layers for converting the output of ResNet to predicates and a varying amount of output neurons, corresponding to the estimated number of n-arity predicates. The network was pretrained on the ImageNet dataset. The policy learning module incorporates the ACE tree learning tool and a wrapper in Prolog.

Our example domain consists of 2-4 cubes colored in red, blue, green, and yellow and randomly stacked on top of each other in a virtual 3D environment. The dataset used for training and testing contains a total of 30000 elements, each with an image of the scene, the correct predicates, a list of blocks that are present and the corresponding expert action, that would lead to stacking the blocks to a tower.

- Participants: Florian Golemo, Manuel Lopes and Thibaut Munzer
- Contact: Florian Golemo

6.25. S-RL Toolbox

Reinforcement Learning (RL) and State Representation Learning (SRL) for Robotics

KEYWORDS: Machine learning - Robotics

FUNCTIONAL DESCRIPTION: This repository was made to evaluate State Representation Learning methods using Reinforcement Learning. It integrates (automatic logging, plotting, saving, loading of trained agent) various RL algorithms (PPO, A2C, ARS, ACKTR, DDPG, DQN, ACER, CMA-ES, SAC, TRPO) along with different SRL methods (see SRL Repo) in an efficient way (1 Million steps in 1 Hour with 8-core cpu and 1 Titan X GPU).

- Partner: ENSTA
- Contact: David Filliat
- URL: https://github.com/araffin/robotics-rl-srl

6.26. Sets

KEYWORD: Data structures
FUNCTIONAL DESCRIPTION: The sets library allow to manipulate and operate on sets.

Those can be simple sets: + Empty: + Singleton: 'a' + Finite: 'a', 'b' + Integer subset: |[1, 10]| + Reals subset: [1, inf[Or, they can be cartesian product of sets: + 'a', 'b' x |[0, 10]| x]-inf, inf[Or, they can be incomplete unions of sets: + 'a','b' x |[0, 5]| U 'c' x -|[0, 10]|

In particular, every set is hashable. This operation is non-trivial in the case of an incomplete union (equivalent to an orthogonal polyhedron). An extreme vertices representations, corresponding to the state-of-the-art, is used to implement it.

Various operations are available: + Product (Cartesian) + Measure + Partition + Belonging test + Subset test (Proper) + Equality test + Union + Intersection + Exclusion

- Contact: Alexandre Pere

6.27. Deep-Explauto

KEYWORDS: Deep learning - Unsupervised learning - Learning - Experimentation
FUNCTIONAL DESCRIPTION: Until recently, curiosity driven exploration algorithms were based on classic learning algorithms, unable to handle large dimensional problems (see explauto). Recent advances in the field of deep learning offer new algorithms able to handle such situations.

Deep explauto is an experimental library, containing reference implementations of curiosity driven exploration algorithms. Given the experimental aspect of exploration algorithms, and the low maturity of the libraries and algorithms using deep learning, proposing black-box implementations of those algorithms, enabling a blind use of those, seem unrealistic.

Nevertheless, in order to quickly launch new experiments, this library offers an set of objects, functions and examples, allowing to kickstart new experiments.

- Contact: Alexandre Pere

6.28. Orchestra

KEYWORD: Experimental mechanics
FUNCTIONAL DESCRIPTION: Ochestra is a set of tools meant to help in performing experimental campaigns in computer science. It provides you with simple tools to:

+ Organize a manual experimental workflow, leveraging git and lfs through a simple interface. + Collaborate with other peoples on a single experimental campaign. + Execute pieces of code on remote hosts such as clusters or clouds, in one line. + Automate the execution of batches of experiments and the presentation of the results through a clean web ui.

A lot of advanced tools exists on the net to handle similar situations. Most of them target very complicated workflows, e.g. DAGs of tasks. Those tools are very powerful but lack the simplicity needed by newcomers. Here, we propose a limited but very simple tool to handle one of the most common situation of experimental campaigns: the repeated execution of an experiment on variations of parameters.

In particular, we include three tools: + expegit: a tool to organize your experimental campaign results in a git repository using git-lfs (large file storage). + runaway: a tool to execute code on distant hosts parameterized with easy to use file templates. + orchestra: a tool to automate the use of the two previous tools on large campaigns.

- Contact: Alexandre Pere

<h1 style="color:red; text-align:center">HEPHAISTOS Project-Team</h1>

6. New Software and Platforms

6.1. ALIAS

Algorithms Library of Interval Analysis for Systems

FUNCTIONAL DESCRIPTION: The ALIAS library whose development started in 1998, is a collection of procedures based on interval analysis for systems solving and optimization.

ALIAS is made of two parts:

ALIAS-C++ : the C++ library (87 000 code lines) which is the core of the algorithms

ALIAS-Maple : the Maple interface for ALIAS-C++ (55 000 code lines). This interface allows one to specify a solving problem within Maple and get the results within the same Maple session. The role of this interface is not only to generate the C++ code automatically, but also to perform an analysis of the problem in order to improve the efficiency of the solver. Furthermore, a distributed implementation of the algorithms is available directly within the interface.

- Participants: Jean-Pierre Merlet and Odile Pourtallier
- Contact: Jean-Pierre Merlet

6.2. PALGate

KEYWORDS: Health - Home care - Handicap

- Contact: David Daney

6.3. Platforms

6.3.1. *ALIAS, Algorithms Library of Interval Analysis for Systems*

Participants: Hiparco Lins Vieira, Jean-Pierre Merlet [correspondant], Yves Papegay.

URL: http://www-sop.inria.fr/hephaistos/developpements/main.html

The ALIAS library whose development started in 1998, is a collection of procedures based on interval analysis for systems solving and optimization.

ALIAS is made of two parts:

ALIAS-C++ : the C++ library (87 000 code lines) which is the core of the algorithms

ALIAS-Maple : the Maple interface for ALIAS-C++ (55 000 code lines). This interface allows one to specify a solving problem within Maple and get the results within the same Maple session. The role of this interface is not only to generate the C++ code automatically, but also to perform an analysis of the problem in order to improve the efficiency of the solver. Furthermore, a distributed implementation of the algorithms is available directly within the interface.

6.3.2. *Hardware platforms*

We describe here only the new platforms that have been developed or improved in 2018 while we maintain a very large number of platforms (e.g. the cable-driven parallel robots of the MARIONET family, the ANG family of walking aids or our experimental flat).

6.3.2.1. REVMED: virtual reality and rehabilitation

Inria and Université Côte d'Azur have agreed to fund us for developing the platform REVMED whose purpose is to introduce end-user motion and their analysis in a virtual reality environment in order to make rehabilitation exercises more attractive and more appropriate for the rehabilitation process. For example we have developed an active treadmill whose slope change according to the user place in the virtual world while the lateral inclination may be changed in order to regulate the load between the left and right leg. Such a system may be used in rehabilitation to simulate a walk in the mountain while increasing on-demand the load on an injured leg (that is usually avoided by the user) for a shorter rehabilitation time. At the same time the walking pattern is analyzed by using lidar, kinect and distance sensor in order to assess the efficiency of the rehabilitation exercise.

The motion system is composed of two vertical columns whose height may be adjusted (they are used for actuating the treadmill), a 6 d.o.f motion base and a cable-driven parallel robot which may lift the user (in the walking experiment this robot may be used to support partly the user while he is walking allowing frail people to start the rehabilitation earlier). We intend to develop sailing and ski simulators as additional rehabilitation environment. Currently the columns and instrumented treadmill are effective and we have completed at the end of this year the coupling between the subject motion and the 2D visualization of a walk in a nice-looking environment, including basic sound (figure 1). Walking analysis is performed using a lidar, a kinect and a distance sensor at the head of the treadmill.

Figure 1. Our rehabilitation station in a configuration with a treadmill, 2 columns for changing its slope and inclination and lidar and kinect for motion analysis

6.3.2.2. Activities detection platform

For non intrusive activities detection we use low cost distance and motion sensors that are incorporated in a 3D printed box and constitute a detection station. Several such station are implemented at appropriate place in the location that has to be monitored. Currently we have 15 such stations deployed at Valrose EHPAD since end of 2016 and 17 (which amount to 77 different sensors) deployed at Institut Claude Pompidou since the end of 2017.

LARSEN Project-Team

6. New Software and Platforms

6.1. Limbo

LIbrary for Model-based Bayesian Optimization

KEYWORDS: Black-box optimization - C++ - Global optimization - Machine learning - Policy Learning - Bayesian optimization - Gaussian processes

FUNCTIONAL DESCRIPTION: Limbo is an open-source C++11 library for Gaussian processes and Bayesian Optimization which is designed to be both highly flexible and very fast. It can be used to optimize functions for which the gradient is unknown, evaluations are expensive, and where runtime cost matters (e.g., on embedded systems or robots). Benchmarks on standard functions show that Limbo is about 2 times faster than BayesOpt (another C++ library) for a similar accuracy.

NEWS OF THE YEAR: - publication of a paper in the Journal of Open Source Software - several bug fixes and performance improvement

- Partners: UPMC - Imperial College London
- Contact: Jean-Baptiste Mouret
- Publication: Limbo: A Flexible High-performance Library for Gaussian Processes modeling and Data-Efficient Optimization
- URL: http://www.resibots.eu/limbo

6.2. sferes2

A lightweight generic C++ framework for evolutionary computation

KEYWORDS: Evolutionary Algorithms - Evolution - Global optimization - Multi-objective optimisation

FUNCTIONAL DESCRIPTION: Sferes2 is a high-performance, multi-core, lightweight, generic C++11 framework for evolutionary computation. It is intently kept small to stay reliable and understandable.

Sferes2 relies heavily on template-based meta-programming in C++ to get both abstraction and execution speed.

NEWS OF THE YEAR: - integration of a new set of classes for quality diversity, based on Antoine Cully's paper (IEEE TEC, 2018) - new documentation in Sphinx - new random generator (more thread safe, C++11) - drop the C++98 support (now C++11 only)

- Partner: UPMC
- Contact: Jean-Baptiste Mouret
- Publication: Sferes_v2: Evolvin' in the Multi-Core World
- URL: http://github.com/sferes2/sferes2/

6.3. xsens_driver

KEYWORD: IMU driver

FUNCTIONAL DESCRIPTION: This is a driver for the third and fourth generation of Xsens IMU devices. The driver is in two parts, a small implementation of most of the MT protocol in Python and a ROS node. It works both on serial and USB interfaces.

These MT* devices can store their configuration and will retrieve it at each boot and then stream data according to this configuration. The node only forwards the data streamed onto ROS topics. In order to configure your device, you can use the mtdevice.py script (or the vendor tool on Windows).

RELEASE FUNCTIONAL DESCRIPTION: bug fixes

NEWS OF THE YEAR: version 2.1.0 (2017-04-14) - several bugfixes and a new option.

- Contact: Francis Colas
- URL: https://github.com/ethz-asl/ethzasl_xsens_driver

6.4. SeekPlans

KEYWORDS: Robotics - Depth map

FUNCTIONAL DESCRIPTION: The SeekPlanes software is a high-performance C99 micro library which seeks planes in a depth image. It provides the height, the pitch and the roll of the camera that takes the image, in order to use the same orthonormal model for multi-camera acquisition. In addition, this library provides all the image planes: walls, ceiling, but also the top of a table or a bed, etc. Ultra fast, written in full portable C99 with optional X86 vectorizations (SSE and/or AVX), it has been tested on Linux and Windows, in 32 and 64 bits, and also on a Raspberry PI model 3.

- Contact: François Charpillet

PERVASIVE Project-Team

6. New Software and Platforms

6.1. Platforms

The AmiQual4Home Innovation Factory is an open research facility for innovation and experimentation with human-centered services based on the use of large-scale deployment of interconnected digital devices capable of perception, action, interaction and communication. The Innovation Factory is composed of a collection of workshops for rapid creation of prototypes, surrounded by a collection of living labs and supported by an industrial innovation and transfer service. Creation of the Innovation Factory has been made possible by a grant from French National programme Investissement d'avenir, together with substantial contributions of resources by Grenoble INP, Univ Joseph Fourier, UPMF, CNRS, Schneider Electric and the Communaute de Communes of Montbonnot. The objective is to provide the academic and industrial communities with an open platform to enable research on design, integration and evaluation of systems and services for smart habitats.

The AmiQual4Home Innovation Factory is a unique combination of three different innovation instruments:

1. Workshops for rapid prototyping of devices that embed perception, action, interaction and communication in ordinary objects based on the MIT FabLab model,

2. Facilities for real-world test and evaluation of devices and services organized as open Living Labs,

3. Resources for assisting students, researchers, entrepreneurs and industrial partners in creating new economic activities.

The AmiQual4Home Innovation Factory works with the Inovallee TARMAC technology incubator as well as the SAT Linksium to proved innovation and transfer services to enable students, researchers and local entrepreneurs to create and grow new commercial activities based on smart objects and services.

<p style="text-align:center">**RAINBOW Project-Team**</p>

6. New Software and Platforms

6.1. bib2html

Latex bibliography generator

KEYWORDS: LaTeX - Bibliography

FUNCTIONAL DESCRIPTION: The purpose of this software is to automatically produce html pages from BibTEX files, and to provide access to the BibTEX entries by several criteria: year of publication, category of publication, keywords, author name. Moreover cross-linking is generating between pages to provide an easy navigation through the pages without going back to the index.

- Partners: Inria - Université de Rennes 1
- Contact: Éric Marchand
- URL: http://www.irisa.fr/lagadic/soft/bib2html/bib2html.html

6.2. HandiViz

Driving assistance of a wheelchair

KEYWORDS: Health - Persons attendant - Handicap

FUNCTIONAL DESCRIPTION: The HandiViz software proposes a semi-autonomous navigation framework of a wheelchair relying on visual servoing.

It has been registered to the APP ("Agence de Protection des Programmes") as an INSA software (IDDN.FR.001.440021.000.S.P.2013.000.10000) and is under GPL license.

- Participants: François Pasteau and Marie Babel
- Partner: INSA Rennes
- Contact: Marie Babel

6.3. SINATRACK

Model-based visual tracking of complex objects

KEYWORDS: Computer vision - Robotics

FUNCTIONAL DESCRIPTION: Sinatrack is a tracking software that allows the 3D localization (translation and rotation) of an object with respect to a monocular camera. It allows to consider object with complex shape. The underlying approach is a model-based tracking techniques. It has been developed for satellite localization and on-orbit service applications but is also suitable for augmented reality purpose.

- Participants: Antoine Guillaume Petit, Éric Marchand and François Chaumette
- Partners: Inria - Université de Rennes 1
- Contact: Éric Marchand

6.4. UsTk

Ultrasound toolkit for medical robotics applications guided from ultrasound images

KEYWORDS: Echographic imagery - Image reconstruction - Medical robotics - Visual tracking - Visual servoing (VS) - Needle insertion

FUNCTIONAL DESCRIPTION: UsTK, standing for Ultrasound Toolkit, is a cross-platform extension of ViSP software dedicated to two- (2D) and three-dimensional (3D) ultrasound image processing and visual servoing based on ultrasound images. Written in C++, UsTK architecture provides a core module that implements all the data structures at the heart of UsTK, a grabber module that allows to acquire ultrasound images from an Ultrasonix or a Sonosite device, a GUI module to display data, an IO module for providing functionalities to read/write data from a storage device, and a set of image processing modules to compute the confidence map of ultrasound images, generate elastography images, track a flexible needle in sequences of 2D and 3D ultrasound images and track a target image template in sequences of 2D ultrasound images. All these modules were implemented on several robotic demonstrators to control the motion of an ultrasound probe or a flexible needle by ultrasound visual servoing.

- Participants: Alexandre Krupa, Marc Pouliquen, Fabien Spindler and Pierre Chatelain
- Partners: Inria - Université de Rennes 1
- Contact: Alexandre Krupa
- URL: https://ustk.inria.fr

6.5. ViSP

Visual servoing platform

KEYWORDS: Augmented reality - Computer vision - Robotics - Visual servoing (VS) - Visual tracking

SCIENTIFIC DESCRIPTION: Since 2005, we develop and release ViSP [1], an open source library available from https://visp.inria.fr. ViSP standing for Visual Servoing Platform allows prototyping and developing applications using visual tracking and visual servoing techniques at the heart of the Rainbow research. ViSP was designed to be independent from the hardware, to be simple to use, expandable and cross-platform. ViSP allows to design vision-based tasks for eye-in-hand and eye-to-hand visual servoing that contains the most classical visual features that are used in practice. It involves a large set of elementary positioning tasks with respect to various visual features (points, segments, straight lines, circles, spheres, cylinders, image moments, pose...) that can be combined together, and image processing algorithms that allow tracking of visual cues (dots, segments, ellipses...) or 3D model-based tracking of known objects or template tracking. Simulation capabilities are also available.

[1] E. Marchand, F. Spindler, F. Chaumette. ViSP for visual servoing: a generic software platform with a wide class of robot control skills. IEEE Robotics and Automation Magazine, Special Issue on "Software Packages for Vision-Based Control of Motion", P. Oh, D. Burschka (Eds.), 12(4):40-52, December 2005.

FUNCTIONAL DESCRIPTION: ViSP provides simple ways to integrate and validate new algorithms with already existing tools. It follows a module-based software engineering design where data types, algorithms, sensors, viewers and user interaction are made available. Written in C++, ViSP is based on open-source cross-platform libraries (such as OpenCV) and builds with CMake. Several platforms are supported, including OSX, iOS, Windows and Linux. ViSP online documentation allows to ease learning. More than 300 fully documented classes organized in 17 different modules, with more than 380 examples and 82 tutorials are proposed to the user. ViSP is released under a dual licensing model. It is open-source with a GNU GPLv2 or more recent license. A professional edition license that replaces GNU GPLv2 is also available.

- Participants: Aurélien Yol, Éric Marchand, Fabien Spindler, François Chaumette and Souriya Trinh
- Partners: Inria - Université de Rennes 1
- Contact: Fabien Spindler
- URL: http://visp.inria.fr

6.6. Platforms

6.6.1. *Robot Vision Platform*

Participants: François Chaumette, Fabien Spindler [contact].

We exploit two industrial robotic systems built by Afma Robots in the nineties to validate our researches in visual servoing and active vision. The first one is a 6 DoF Gantry robot, the other one is a 4 DoF cylindrical robot (see Fig. 2). These robots are equipped with cameras. The Gantry robot also allows embedding grippers on its end-effector.

Note that 3 papers [53], [78], [10] and 1 PhD Thesis [2] published by Rainbow in 2018 include results validated on this platform.

Figure 2. Rainbow robotics platform for vision-based manipulation

6.6.2. Mobile Robots

Participants: Marie Babel, Solenne Fortun, François Pasteau, Fabien Spindler [contact].

For fast prototyping of algorithms in perception, control and autonomous navigation, the team uses a Pioneer 3DX from Adept (see Fig. 3 .a). This platform is equipped with various sensors needed for autonomous navigation and sensor-based control.

Moreover, to validate our research in personally assisted living topic (see Section 7.4.3), we have three electric wheelchairs, one from Permobil, one from Sunrise and the last from YouQ (see Fig. 3 .b). The control of the wheelchair is performed using a plug and play system between the joystick and the low level control of the wheelchair. Such a system lets us acquire the user intention through the joystick position and control the wheelchair by applying corrections to its motion. The wheelchairs have been fitted with cameras and ultrasound sensors to perform the required servoing for assisting handicapped people. This year we also bought a wheelchair haptic simulator to develop new human interaction strategies in an virtual reality environment (Fig. 3 (c)).

Note that 4 papers exploiting the mobile robots were published this year [23], [60], [79], [80].

6.6.3. Medical Robotic Platform

Participants: Alexandre Krupa, Marc Pouliquen, Fabien Spindler [contact].

This platform is composed of two 6 DoF Adept Viper arms (see Fig. 4 .a). Ultrasound probes connected either to a SonoSite 180 Plus or an Ultrasonix SonixTouch imaging system can be mounted on a force torque sensor attached to each robot end-effector. The haptic Virtuose 6D device (see Fig. 8 .a) can also be used within this platform.

(a)   (b)   (c)

Figure 3. Mobile Robot Platform. a) Pioneer P3-DX robot, b) wheelchairs from Permobil, Sunrise and YouQ, c) the wheelchair haptic simulator.

This testbed is of primary interest for researches and experiments concerning ultrasound visual servoing applied to probe positioning, soft tissue tracking, elastography or robotic needle insertion tasks (see Section 7.2.9).

This platform was used to obtain experimental results presented in 6 articles [18], [61], [12], [10], [36], [51] and in 2 PhD manuscripts [4], [5] published this year.

(a)   (b)
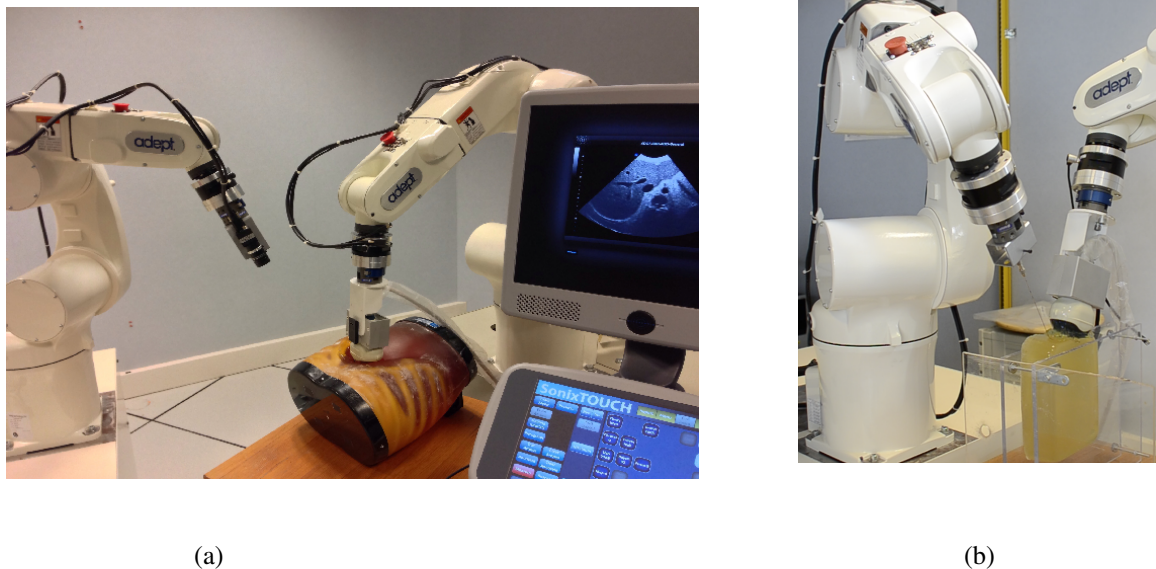
Figure 4. Rainbow medical robotic platforms. a) On the right Viper S850 robot arm equipped with a SonixTouch 3D ultrasound probe. On the left Viper S650 equipped with a tool changer that allows to attach a classical camera or biopsy needles. b) Robotic setup for autonomous needle insertion by visual servoing.

6.6.4. Advanced Manipulation Platform

Participants: François Chaumette, Claudio Pacchierotti, Paolo Robuffo Giordano, Fabien Spindler [contact].

This new platform is composed by 2 Panda lightweight arms from Franka Emika equipped with torque sensors in all seven axes. An electric gripper, a camera or a soft hand from qbrobotics can be mounted on the robot end-effector (see Fig. 5) to validate our researches in coupling force and vision for controlling robot manipulators (see Section 7.2.13) and in shared control for remote manipulation (see Section 7.4.1). Other haptic devices (see Section 6.6.7) can also be coupled to this platform.

Note that 1 paper published this year include experimental results obtained with new platform [77].

Figure 5. Rainbow advanced manipulation platform. One of the two Panda lightweight arms from Franka Emika, with mounted the Pisa SoftHand.

6.6.5. *Humanoid Robots*

Participants: François Chaumette, Julien Pettré, Fabien Spindler [contact].

Romeo is a humanoid robot from SoftBank Robotics which is intended to be a genuine personal assistant and companion. Only the upper part of the body (trunk, arms, neck, head, eyes) is working. This research platform is used to validate our researches in visual servoing and visual tracking for object manipulation (see Fig. 6 .a).

Pepper, another human-shaped robot designed by SoftBank Robotics to be a genuine day-to-day companion (see Fig. 6 .b) is also part of this platform. It has 17 DoF mounted on a wheeled holonomic base and a set of sensors (cameras, laser, ultrasound, inertial, microphone) that makes this platform interesting for robot-human interactions during locomotion (see Section 7.2.5).

Note that 2 papers published this year include experimental results obtained with this platform [24], [23].

6.6.6. *Unmanned Aerial Vehicles (UAVs)*

Participants: Pol Mordel, Paolo Robuffo Giordano, Fabien Spindler [contact].
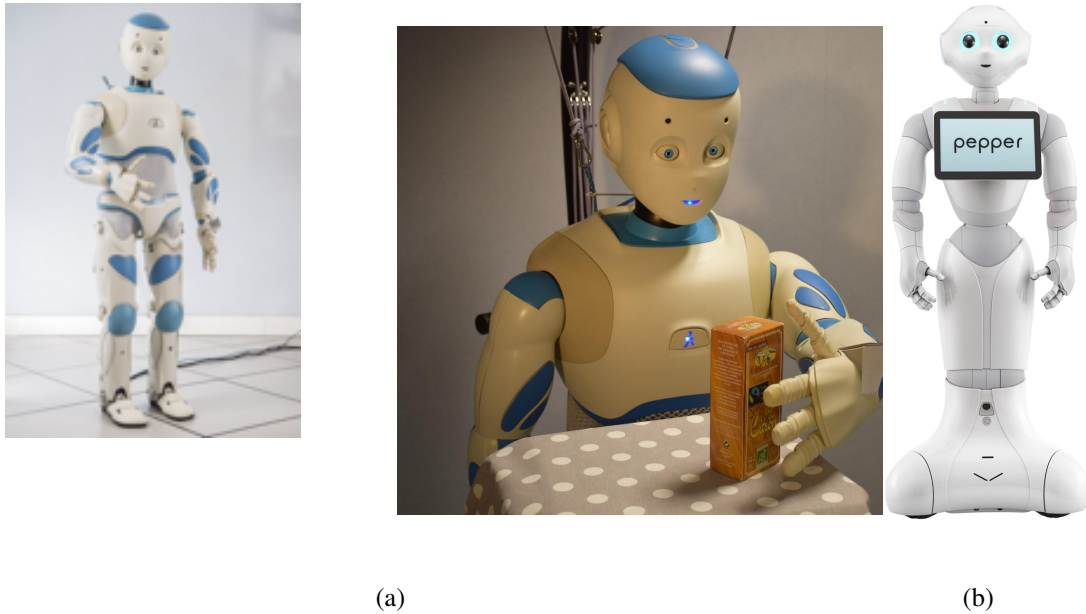
(a) (b)

Figure 6. Humanoid Robots Platform. a) Romeo experimental platform, b) Pepper human-shaped robot

From 2014, Rainbow also started some activities involving perception and control for single and multiple quadrotor UAVs, especially thanks to the ANR project "SenseFly" (see Section 9.2.1). To this end, we purchased four quadrotors from Mikrokopter Gmbh, Germany (see Fig. 7 .a), and one quadrotor from 3DRobotics, USA (see Fig. 7 .b). The Mikrokopter quadrotors have been heavily customized by: (i) reprogramming from scratch the low-level attitude controller onboard the microcontroller of the quadrotors, (ii) equipping each quadrotor with a NVIDIA Jetson TX2 board running Linux Ubuntu and the TeleKyb-3 software based on genom3 framework developed at LAAS in Toulouse (the middleware used for managing the experiment flows and the communication among the UAVs and the base station), and (iii) purchasing the Flea Color USB3 cameras together with the gimbal needed to mount them on the UAVs. The quadrotor group is used as robotic platforms for testing a number of single and multiple flight control schemes with a special attention on the use of onboard vision as main sensory modality.

This year 7 papers [33], [34], [65], [67], [72], [17], [71] and 1 PhD Thesis [7] contain experimental results obtained with this platform.

6.6.7. *Haptics and Shared Control Platform*

Participants: Claudio Pacchierotti, Paolo Robuffo Giordano, Fabien Spindler [contact].

Various haptic devices are used to validate our research in shared control. We have a Virtuose 6D device from Haption (see Fig. 8 .a). This device is used as master device in many of our shared control activities (see Sections 9.3.1.3 , 7.2.10 , and 7.3.1). It could also be coupled to the Haption haptic glove in loan from the University of Birmingham. An Omega 6 (see Fig. 8 .b) from Force Dimension, devices in loan from Ultrahaptics as well as a soft hand from qbrobotics complete this platform that could be coupled to the other robotic platforms.

This platform was used to obtain experimental results presented in 2 articles [51], [36] and in 1 PhD manuscript [5] published this year.

<center>(a)</center>

<center>(b)</center>

Figure 7. Unmanned Aerial Vehicles Platform. a) Quadrotor XL1 from Mikrokopter, b) Quadrotor Iris from 3DRobotics

<center>(a)</center>

<center>(b)</center>

Figure 8. Haptics and Shared Control Platform. a) Virtuose 6D and b) Omega 6 haptic devices

<div align="center">

RITS Project-Team

</div>

6. New Software and Platforms

6.1. PML-SLAM

KEYWORD: Localization
SCIENTIFIC DESCRIPTION: Simultaneous Localization and Mapping method based on 2D laser data.

- Participants: Fawzi Nashashibi and Zayed Alsayed
- Contact: Fawzi Nashashibi

6.2. V2Provue

Vehicle-to-Pedestrian
FUNCTIONAL DESCRIPTION: It is a software developed for the Vehicle-to-Pedestrian (V2P) communications, risk calculation, and alarming pedestrians of collision risk. This software is made of an Android application dedicated to pedestrians and RtMaps modules for the vehicles.

On the pedestrian side, the application is relying on GPS data to localize the user and Wi-Fi communications are used to receive messages about close vehicles and send information about the pedestrian positioning. Besides, a service has been developed to evaluate the collision risk with the vehicles near the pedestrian and an HMI based on OpenStreetMap displays all the useful information such as pedestrian and vehicles localization and, collision risk.

On the vehicle side, RtMaps modules allowing V2X communications have been developed. These modules contain features such as TCP/UDP socket transmissions, broadcast, multicast, unicast communications, routing, forwarding algorithms, and application specific modules. In the V2ProVu software, a particular application module has been implemented to create data packets containing information about the vehicle state (position, speed, yaw rate,...) and the V2X communication stack is used to broadcast these packets towards pedestrians. Moreover, the V2proVu application can also receive data from pedestrians and create objects structures that can be shared with the vehicle perception tools.

- Contact: Fawzi Nashashibi

6.3. SimConVA

Connected Autonomous Vehicles Simulator
FUNCTIONAL DESCRIPTION: The software provides an interface between the network simulator ns-3 (https://www.nsnam.org/) and the modular prototyping framework RTMaps (https://intempora.com/).

This code allows to create an RTMaps component which activates and controls the ns-3 simulator. The component handles the sending and reception of data packets between ns-3 and RTMaps for each vehicle. It also handles the mobility of vehicles in ns-3 using their known position in RTMaps.

- Authors: Pierre Merdrignac, Oyunchimeg Shagdar and Jean-Marc Lasgouttes
- Contact: Jean-Marc Lasgouttes

LINKMEDIA Project-Team (section vide)

<h1 style="text-align:center; color:red">MAGRIT Project-Team</h1>

6. New Software and Platforms

6.1. PoLAR

Portable Library for Augmented Reality

FUNCTIONAL DESCRIPTION: PoLAR (Portable Library for Augmented Reality) is a framework which aims to help creating graphical applications for augmented reality, image visualization and medical imaging. PoLAR was designed to offer powerful visualization functionalities without the need to be a specialist in Computer Graphics. The framework provides an API to state-of-the-art libraries: Qt to build GUIs and OpenSceneGraph for high-end visualization, for researchers and engineers with a background in Computer Vision to be able to create beautiful AR applications, with little programming effort. The framework is written in C++ and published under the GNU GPL license

- Contact: Erwan Kerrien
- URL: http://polar.inria.fr

6.2. Fast>VP

KEYWORDS: Vanishing points - Image rectification

FUNCTIONAL DESCRIPTION: Fast>VP is a fast and effective tool to detect vanishing points in uncalibrated images of urban or indoor scenes.

This tool also allows automatic rectification of the vertical planes in the scene, namely generating images where these planes appear as if they were observed from a fronto-parallel view.

It is the Matlab implementation of the algorithm described in [6].

- Contact: Gilles Simon
- URL: https://members.loria.fr/GSimon/fastvp/

6.3. NoLoDuDoCT

A non-local dual-domain cartoon and texture decomposition

KEYWORDS: Image analysis - Cartoon and texture decomposition

FUNCTIONAL DESCRIPTION: This is an algorithm decomposing images into cartoon and texture components. Spectrum components of textures are detected on the basis of a statistical hypothesis test, the null hypothesis modeling a purely cartoon patch. Statistics are estimated in a non-local way.

- Contact: Frédéric Sur
- URL: https://members.loria.fr/FSur/software/NoLoDuDoCT/

6.4. BSpeckleRender

A Boolean model for deformed speckle rendering

KEYWORDS: Boolean model - Monte Carlo estimation - Experimental mechanics - Displacement fields

FUNCTIONAL DESCRIPTION: This library implements a new method for synthesizing speckle images deformed by an arbitrary deformation field set by the user. Such images are very useful for assessing the different methods based on digital image correlation (DIC) for estimating displacement fields in experimental mechanics. Since the deformations are very small, it is necessary to ensure that no additional bias is introduced by the image synthesis algorithm. The proposed method is based on the Monte Carlo evaluation of images generated by a Boolean model.

- Contact: Frédéric Sur
- URL: https://members.loria.fr/FSur/software/BSpeckleRender/

MORPHEO Project-Team

6. New Software and Platforms

6.1. 4D repository

KEYWORDS: 4D - Dynamic scene

FUNCTIONAL DESCRIPTION: This website hosts dynamic mesh sequences reconstructed from images captured using a multi-camera set up. Such mesh-sequences offer a new promising vision of virtual reality, by capturing real actors and their interactions. The texture information is trivially mapped to the reconstructed geometry, by back-projecting from the images. These sequences can be seen from arbitrary viewing angles as the user navigates in 4D (3D geometry + time) . Different sequences of human / non-human interaction can be browsed and downloaded from the data section.

- Contact: Edmond Boyer
- URL: http://4drepository.inrialpes.fr/

6.2. Lucy Viewer

KEYWORDS: Data visualization - 4D - Multi-Cameras

SCIENTIFIC DESCRIPTION: Lucy Viewer is an interactive viewing software for 4D models, i.e, dynamic three-dimensional scenes that evolve over time. Each 4D model is a sequence of meshes with associated texture information, in terms of images captured from multiple cameras at each frame. Such data is available from the 4D repository website hosted by Inria Grenoble.

With Lucy Viewer, the user can use the mouse to zoom in onto the 4D models, zoom out, rotate, translate and view from an arbitrary angle as the 4D sequence is being played. The texture information is read from the images at each frame in the sequence and applied onto the meshes. This helps the user visualize the 3D scene in a realistic manner. The user can also freeze the motion at a particular frame and inspect a mesh in detail. Lucy Viewer lets the user to also select a subset of cameras from which to apply texture information onto the meshes. The supported formats are meshes in .OFF format and associated images in .PNG or .JPG format.

FUNCTIONAL DESCRIPTION: Lucy Viewer is an interactive viewing software for 4D models, i.e, dynamic three-dimensional scenes that evolve over time. Each 4D model is a sequence of meshes with associated texture information, in terms of images captured from multiple cameras at each frame.

- Participants: Edmond Boyer, Jean-Sébastien Franco, Matthieu Armando and EYMERIC AMSELEM
- Contact: Edmond Boyer
- URL: https://kinovis.inria.fr/lucyviewer/

6.3. Shape Tracking

FUNCTIONAL DESCRIPTION: We are developing a software suite to track shapes over temporal sequences. The motivation is to provide temporally coherent 4D Models, i.e. 3D models and their evolutions over time , as required by motion related applications such as motion analysis. This software takes as input a temporal sequence of 3D models in addition to a template and estimate the template deformations over the sequence that fit the observed 3D models.

- Contact: Edmond Boyer

6.4. QuickCSG V2

KEYWORDS: 3D modeling - CAD - 3D reconstruction - Geometric algorithms

SCIENTIFIC DESCRIPTION: See the technical report "QuickCSG: Arbitrary and Faster Boolean Combinations of N Solids", Douze, Franco, Raffin.

The extension of the algorithm to self-intersecting meshes is described in "QuickCSG with self-intersections", a document inside the package.

FUNCTIONAL DESCRIPTION: QuickCSG is a library and command-line application that computes Boolean operations between polyhedra. The basic algorithm is described in the research report "QuickCSG: Arbitrary and Faster Boolean Combinations of N Solids", Douze, Franco, Raffin. The input and output polyhedra are defined as indexed meshes. In version 2, that was developed in the context of a software transfer contract, the meshes can be self-intersecting, in which case the inside and outside are defined by the non-zero winding rule. The operation can be any arbitrary Boolean function, including one that is defined as a CSG tree. The focus of QuickCSG is speed. Robustness to degeneracies is obtained by carefully applied random perturbations.

- Authors: Matthys Douze, Jean-Sébastien Franco and Bruno Raffin
- Contact: Jean-Sébastien Franco
- URL: https://kinovis.inria.fr/quickcsg/

6.5. CVTGenerator

KEYWORDS: Mesh - Centroidal Voronoi tessellation - Implicit surface
FUNCTIONAL DESCRIPTION: CVTGenerator is a program to build Centroidal Voronoi Tessellations of any 3D meshes and implicit surfaces.
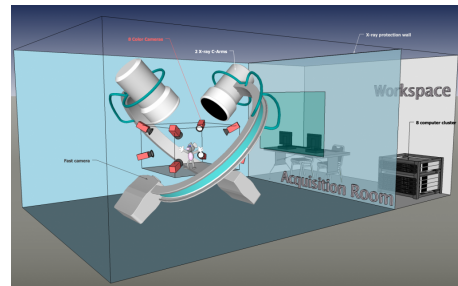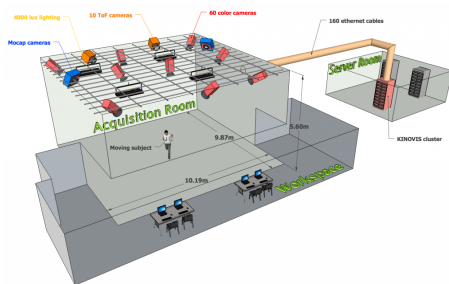
- Partner: INP Grenoble
- Contact: Li Wang
- URL: http://cvt.gforge.inria.fr/

6.6. Kinovis Platform

Figure 2. Kinovis platforms: on the left the Inria platform; on the right Grenoble Hospital platform.

Kinovis (http://kinovis.inrialpes.fr/) is a multi-camera acquisition project that was selected within the call for proposals "Equipements d'Excellence" of the program "Investissement d'Avenir" funded by the French government. The project involves 2 institutes: the Inria Grenoble Rhône-Alpes, the Université Joseph Fourier and 4 laboratories: the LJK (laboratoire Jean Kuntzmann - applied mathematics), the LIG (Laboratoire d'informatique de Grenoble - Computer Science), the Gipsa lab (Signal, Speech and Image processing) and the LADAF (Grenoble Hospitals - Anatomy). The Kinovis environment is composed of 2 complementary platforms (see Figure 2). A first platform located at Inria Grenoble with a 10mx10m acquisition surface is equipped with 68 color cameras and 20 IR motion capture (mocap) cameras. It is the evolution of the Grimage platform towards the production of better models of more complex dynamic scenes. A second platform located at Grenoble Hospitals (CHU), within the LADAF anatomy laboratory, is equipped with 10 color and 2 X-ray cameras to enable combined analysis of internal and external shape structures, such as skeletons and their surrounding bodies. Both platforms have already demonstrated their potential through a range of projects lead by the team and externally. Members of Morpheo are highly involved in this project. Edmond Boyer is coordinating this project, and Julien Pansiot is managing the technical resources of both platforms.

PERCEPTION Project-Team

5. New Software and Platforms

5.1. ECMPR

Expectation Conditional Maximization for the Joint Registration of Multiple Point Sets
FUNCTIONAL DESCRIPTION: Rigid registration of two or several point sets based on probabilistic matching between point pairs and a Gaussian mixture model

- Participants: Florence Forbes, Manuel Yguel and Radu Horaud
- Contact: Patrice Horaud
- URL: https://team.inria.fr/perception/research/jrmpc/

5.2. Mixcam

Reconstruction using a mixed camera system
KEYWORDS: Computer vision - 3D reconstruction
FUNCTIONAL DESCRIPTION: We developed a multiple camera platform composed of both high-definition color cameras and low-resolution depth cameras. This platform combines the advantages of the two camera types. On one side, depth (time-of-flight) cameras provide coarse low-resolution 3D scene information. On the other side, depth and color cameras can be combined such as to provide high-resolution 3D scene reconstruction and high-quality rendering of textured surfaces. The software package developed during the period 2011-2014 contains the calibration of TOF cameras, alignment between TOF and color cameras, TOF-stereo fusion, and image-based rendering. These software developments were performed in collaboration with the Samsung Advanced Institute of Technology, Seoul, Korea. The multi-camera platform and the basic software modules are products of 4D Views Solutions SAS, a start-up company issued from the PERCEPTION group.

- Participants: Clément Ménier, Georgios Evangelidis, Michel Amat, Miles Hansard, Patrice Horaud, Pierre Arquier, Quentin Pelorson, Radu Horaud, Richard Broadbridge and Soraya Arias
- Contact: Patrice Horaud
- URL: https://team.inria.fr/perception/mixcam-project/

5.3. NaoLab

Distributed middleware architecture for interacting with NAO
FUNCTIONAL DESCRIPTION: This software provides a set of librairies and tools to simply the control of NAO robot from a remote machine. The main challenge is to make easy prototuping applications for NAO ising C++ and Matlab programming environments. Thus NaoLab provides a prototyping-friendly interface to retrieve sensor date (video and sound streams, odometric data...) and to control the robot actuators (head, arms, legs...) from a remote machine.This interface is available on Naoqi SDK, developed by Aldebarab company, Naoqi SDK is needed as it provides the tools to acess the embedded NAO services (low-level motor command, sensor data access...)

- Authors: Fabien Badeig, Quentin Pelorson and Patrice Horaud
- Contact: Patrice Horaud
- URL: https://team.inria.fr/perception/research/naolab/

5.4. Stereo matching and recognition library

KEYWORD: Computer vision

FUNCTIONAL DESCRIPTION: Library providing stereo matching components to rectify stereo images, to retrieve faces from left and right images, to track faces and method to recognise simple gestures

- Participants: Jan Cech, Jordi Sanchez-Riera, Radu Horaud and Soraya Arias
- Contact: Soraya Arias
- URL: https://code.humavips.eu/projects/stereomatch

5.5. Platforms

5.5.1. *Audio-Visual Head Popeye+*

In 2016 our audio-visual platform was upgraded from Popeye to Popeye+. Popeye+ has two high-definition cameras with a wide field of view. We also upgraded the software libraries that perform synchronized acquisition of audio signals and color images. Popeye+ has been used for several datasets.
Websites:
https://team.inria.fr/perception/projects/popeye/
https://team.inria.fr/perception/projects/popeye-plus/
https://team.inria.fr/perception/avtrack1/
https://team.inria.fr/perception/avdiar/

5.5.2. *NAO Robots*

The PERCEPTION team selected the companion robot NAO for experimenting and demonstrating various audio-visual skills as well as for developing the concept of social robotics that is able to recognize human presence, to understand human gestures and voice, and to communicate by synthesizing appropriate behavior. The main challenge of our team is to enable human-robot interaction in the real world.

Figure 2. The Popeye+ audio-visual platform (left) delivers high-quality, high-resolution and wide-angle images at 30FPS. The NAO prototype used by PERCEPTION in the EARS STREP project has a twelve-channel spherical microphone array synchronized with a stereo camera pair.

The humanoid robot NAO is manufactured by SoftBank Robotics Europe. Standing, the robot is roughly 60 cm tall, and 35cm when it is sitting. Approximately 30 cm large, NAO includes two CPUs. The first one, placed in the torso, together with the batteries, controls the motors and hence provides kinematic motions with 26 degrees of freedom. The other CPU is placed in the head and is in charge of managing the proprioceptive sensing, the communications, and the audio-visual sensors (two cameras and four microphones, in our case). NAO's on-board computing resources can be accessed either via wired or wireless communication protocols.

NAO's commercially available head is equipped with two cameras that are arranged along a vertical axis: these cameras are neither synchronized nor a significant common field of view. Hence, they cannot be used in combination with stereo vision. Within the EU project HUMAVIPS, Aldebaran Robotics developed a binocular camera system that is arranged horizontally. It is therefore possible to implement stereo vision algorithms on NAO. In particular, one can take advantage of both the robot's cameras and microphones. The cameras deliver VGA sequences of image pairs at 12 FPS, while the sound card delivers the audio signals arriving from all four microphones and sampled at 48 kHz. Subsequently, Aldebaran developed a second binocular camera system to go into the head of NAO v5.

In order to manage the information flow gathered by all these sensors, we implemented several middleware packages. In 2012 we implemented Robotics Services Bus (RSB) developed by the University of Bielefeld. Subsequently (2015-2016) the PERCEPTION team developed NAOLab, a middleware for hosting robotic applications in C, C++, Python and Matlab, using the computing power available with NAO, augmented with a networked PC. In 2017 we abandoned RSB and NAOLab and converted all our robotics software packages to ROS (Robotic Operating System).

Websites:
https://team.inria.fr/perception/nao/
https://team.inria.fr/perception/research/naolab/

<p style="text-align:center">**SIROCCO Project-Team**</p>

6. New Software and Platforms

6.1. QuantizationAE

KEYWORDS: Compression - Machine learning

FUNCTIONAL DESCRIPTION: This code learns an autoencoder to compress images. The learning is performed under a rate-distortion criterion, and jointly learns a transform (the autoencoder) and the quantization step for target rate points.The code is organized as follows. It first builds a set of luminance images (B1) for the auto-encoder training, a set of luminance images (B2) to analyze how the auto-encoder training advances and a set of luminance images (B3) to evaluate the auto-encoders in terms of rate-distortion. It then trains several auto-encoders using a rate-distortion criterion on the set B1. The quantization can be either fixed or learned during this training stage. The set B2 enables to periodically compute indicators to detect overfitting. It finally compares the auto-encoders in terms of rate-distortion on the set B3. The quantization can be either fixed or variable during this test.

- Participants: Aline Roumy, Christine Guillemot and Thierry Dumas
- Contact: Aline Roumy

6.2. LF-Inpainting

Light field inpainting based on a low rank model

KEYWORDS: Light fields - Low rank models - Inpainting

FUNCTIONAL DESCRIPTION: This code implements a method for propagating the inpainting of the central view of a light field to all the other views. To this end, it also implements a new matrix completion algorithm, better suited to the inpainting application than existing methods. A first option does not require any depth prior, unlike most existing light field inpainting algorithms. The code also implements an extended version to better handle the case where the area to inpaint contains depth discontinuities.

- Participants: Mikael Le Pendu and Christine Guillemot
- Contact: Christine Guillemot

6.3. LF-HLRA

Light fields homography-based low rank approximation

KEYWORDS: Compression - Light fields - Low rank models - Dimensionality reduction

FUNCTIONAL DESCRIPTION: This code jointly searches for homographies to align the views of an input light field together with the components of its low rank approximation model. The code either uses a global homography per view or multiple homographies, one per region, the region being extracted using depth information.

- Participants: Xiaoran Jiang, Mikael Le Pendu and Christine Guillemot
- Contact: Christine Guillemot

6.4. GBR-MVimages

Graph-based representation for multi-view and light field images

KEYWORDS: Light fields - Multi-View reconstruction - Graph

FUNCTIONAL DESCRIPTION: Graph-Based Representation (GBR) describes color and geometry of multiview or light field image content using a graph. The graph vertices represent the color information, while the edges represent the geometry information, i.e., the disparity, by connecting corresponding pixels in neighboring images.

- Participants: Xin Su and Thomas Maugey
- Contact: Thomas Maugey

6.5. FastLFInpainting

Fast light field inpainting

KEYWORDS: Inpainting - Light fields

FUNCTIONAL DESCRIPTION: This software implements a method for fast and efficient inpainting of light fields. It computes disparity based on smoothed structure tensors, that is then used for propagating, by angular warping, the inpainted texture of one view to the entire light field. The code allows inpainting a light field of 80 views in a few seconds (from 4 to 15s, depending on the size of the region to be inpainted). The software has been registered at APP under the number IDDN.FR.001.290017.000.S.P.2018.000.21000.

- Participants: Pierre Allain, Laurent Guillo and Christine Guillemot
- Contact: Laurent Guillo

6.6. M360CT

Multi-360 Calibration Toolkit

KEYWORDS: Omnidirectional camera - Calibration - FTV - 6DoF

FUNCTIONAL DESCRIPTION: Based on multiple synchronized sequences of a chessboard pattern moving in the scene, the algorithm computes the internal and external camera parameters of the different cameras under the unified spherical model. This software is composed of two executables, the first one for the individual calibration of each camera, the second one for the fusion of all the outputs of the first executable. The work has been submitted at APP with the number IDNN.FR.001.510008.S.P.2018.000.10800.

- Participants: Cédric Le Cam, Thomas Maugey and Laurent Guillo
- Contact: Thomas Maugey
- URL: http://project.inria.fr/ftv360

6.7. Platforms

6.7.1. *Light field editor*

Participants: Pierre Allain, Laurent Guillo, Christine Guillemot.

As part of the ERC Clim project, the EPI Sirocco is developing a light field editor, a tool analogous to traditional image editors such as the GNU image manipulation program Gimp or the raster graphic editor Photoshop but dedicated to light fields. As input data, this tool accepts for instance sparse light fields acquired with High Density Camera Arrays (HDCA) or denser light fields captured with microlens array (MLA). Two kinds of features are provided. Traditional features such as changing the angle of view, refocusing or depth map extraction are or will be soon supported. More advanced features are being integrated in our tool as libraries we have developed, such as inpainting to support light field manipulations like object removal, and denoising in the 4D ray space. The next steps are to integrate libraries enabling scene depth estimation and view synthesis. The tool and libraries are developed in C++ and the graphical user interface relies on Qt.

6.7.2. *Acquisition of multi-view sequences for Free viewpoint Television*

Participants: Cédric Le Cam, Laurent Guillo, Thomas Maugey.

The scientific and industrial community is nowadays exploring new multimedia applications using 3D data (beyond stereoscopy). In particular, Free viewpoint Television (FTV) has attracted much attention in the recent years. In those systems, the user can choose in real time its view angle from which he/she wants to observe the scene. Despite the great interest for FTV, the lack of realistic and ambitious datasets penalizes the research effort. The acquisition of such sequences is very costly in terms of hardware and working effort, which explains why no multi-view videos suitable for FTV has been proposed yet.

In the project ATeP (funded by Inriahub), we have developed a novel acquisition procedure relying on forty synchronized omnidirectional cameras. The captured content allows an omni-directional visualization of the scene at a set of discrete viewpoints corresponding to the pre-defined camera positions. We also propose a calibration technique to estimate the position and orientation of each camera with respect to a same reference. This solution relies on a calibration of each individual camera, and a graph-based synchronization of all the estimated parameters.

Based on these developed tools, we have built a complete dataset that we share on the following website *https://project.inria.fr/ftv360*. Our dataset is made of two different captures (indoor and outdoor), with, in total 8 different sequences (each of them having 40 synchronized videos of 1 to 4 min long). The calibration parameters are shared with the calibration toolkit that was developed during the project. These data can serve for the development of new tools for FTV, such as: view synthesis, depth estimation, super resolution, inpainting, etc.

6.7.3. *Light fields datasets*
Participants: Pierre Allain, Christine Guillemot, Laurent Guillo.

The EPI Sirocco makes extensive use of light field datasets with sparse or dense contents provided by the scientific community to run tests. However, it has also generated its own natural and synthetic contents.

Natural content has been created with Lytro cameras (the original first generation Lytro and the Lytro Illum). The team also owns a R8 Raytrix plenoptic cameras with which still and video contents have been captured. Applications taking advantage of the Raytrix API have been developed to extract views from the Raytrix lightfield. The number of views per frame is configurable and can be set for instance to 3x3 or 9x9 according to the desired sparsity. A dataset of video light fields captured by our raytrix R8 camera has been proposed to the MPEG-I standardization group and retained for test purposes [24].

Synthetic content exists for dense light fields with small baselines. To address issues of scene depth estimation and of view synthesis in more difficult configurations like in the case of large baselines, we have produced two datasets that we use for training neural networks for scene depth estimation from light fields with small and large baselines. Most of our rendered light field scenes are indoor scenes, with light reflection and diffusion on the object surfaces to make them more realistic. Both dense and sparse light fields of 9×9 views of 512×512 pixels have been rendered from the input 3D models, with a disparity range of $[-20, +20]$ for sparse light fields and $[-4, +4]$ for dense light fields. The dense and sparse light fields datasets contains 43 and 53 scene respectively. They are provided together with the ground truth depth maps.

Similarly, as no publicly available dataset exist for video light fields, we have produced our own data set from the Sintel film (https://durian.blender.org/download/), which is a short computer animated film by the Blender institute, part of the Blender Foundation. A specific Blender add-on is used to extract views from a frame. As previously, the number of views is configurable. Synthetic contents present the advantage to provide a ground truth useful to evaluate how accurate our algorithms are to compute, for instance, the depth maps and the scene flows. At the moment, the dataset contains two synthetic video light fields of 50 frames.

All these contents are made available via the project web site: http://clim.inria.fr/DataSoftware.html

<p align="center" style="color:red">STARS Project-Team</p>

6. New Software and Platforms

6.1. SUP

Scene Understanding Platform

KEYWORDS: Activity recognition - 3D - Dynamic scene

FUNCTIONAL DESCRIPTION: SUP is a software platform for perceiving, analyzing and interpreting a 3D dynamic scene observed through a network of sensors. It encompasses algorithms allowing for the modeling of interesting activities for users to enable their recognition in real-world applications requiring high-throughput.

- Participants: Etienne Corvée, François Brémond, Thanh Hung Nguyen and Vasanth Bathrinarayanan
- Partners: CEA - CHU Nice - USC Californie - Université de Hamburg - I2R
- Contact: François Brémond
- URL: https://team.inria.fr/stars/software

6.2. VISEVAL

FUNCTIONAL DESCRIPTION: ViSEval is a software dedicated to the evaluation and visualization of video processing algorithm outputs. The evaluation of video processing algorithm results is an important step in video analysis research. In video processing, we identify 4 different tasks to evaluate: detection, classification and tracking of physical objects of interest and event recognition.

- Participants: Bernard Boulay and François Brémond
- Contact: François Brémond
- URL: http://www-sop.inria.fr/teams/pulsar/EvaluationTool/ViSEvAl_Description.html

<h1 style="text-align:center; color:red">THOTH Project-Team</h1>

6. New Software and Platforms

6.1. LCR-Net

Localization-Classification-Regression Network for Human Pose

KEYWORDS: Object detection - Recognition of human movement

FUNCTIONAL DESCRIPTION: We propose an end-to-end architecture for joint 2D and 3D human pose estimation in natural images. Key to our approach is the generation and scoring of a number of pose proposals per image, which allows us to predict 2D and 3D pose of multiple people simultaneously. Our architecture contains 3 main components: 1) the pose proposal generator that suggests potential poses at different locations in the image, 2) a classifier that scores the different pose proposals , and 3) a regressor that refines pose proposals both in 2D and 3D.

- Participants: Grégory Rogez, Philippe Weinzaepfel and Cordelia Schmid
- Contact: Grégory Rogez
- Publication: LCR-Net: Localization-Classification-Regression for Human Pose
- URL: https://thoth.inrialpes.fr/src/LCR-Net/

6.2. CKN-seq

Convolutional Kernel Networks for Biological Sequences

KEYWORD: Bioinformatics

SCIENTIFIC DESCRIPTION: The growing amount of biological sequences available makes it possible to learn genotype-phenotype relationships from data with increasingly high accuracy. By exploiting large sets of sequences with known phenotypes, machine learning methods can be used to build functions that predict the phenotype of new, unannotated sequences. In particular, deep neural networks have recently obtained good performances on such prediction tasks, but are notoriously difficult to analyze or interpret. Here, we introduce a hybrid approach between kernel methods and convolutional neural networks for sequences, which retains the ability of neural networks to learn good representations for a learning problem at hand, while defining a well characterized Hilbert space to describe prediction functions. Our method outperforms state-of-the-art convolutional neural networks on a transcription factor binding prediction task while being much faster to train and yielding more stable and interpretable results.

FUNCTIONAL DESCRIPTION: CKN-Seq is a software package for predicting transcription factor binding sites. It was shipped with the BiorXiv preprint

D. Chen, L. Jacob, and J. Mairal. Predicting Transcription Factor Binding Sites with Convolutional Kernel Networks. 2017.

The software is implemented in PyTorch.

- Participants: Laurent Jacob, Dexiong Chen and Julien Mairal
- Partners: CNRS - UGA
- Contact: Julien Mairal
- Publication: Biological Sequence Modeling with Convolutional Kernel Networks
- URL: https://gitlab.inria.fr/dchen/CKN-seq

6.3. Loter

Loter: A software package to infer local ancestry for a wide range of species

KEYWORDS: Local Ancestry Inference - Bioinformatics

SCIENTIFIC DESCRIPTION: Admixture between populations provides opportunity to study biological adaptation and phenotypic variation. Admixture studies can rely on local ancestry inference for admixed individuals, which consists of computing at each locus the number of copies that originate from ancestral source populations. Loter is a software package that does not require any biological parameter besides haplotype data in order to make local ancestry inference available for a wide range of species.

FUNCTIONAL DESCRIPTION: Loter is a Python package for haplotype phasing and local ancestry inference.

NEWS OF THE YEAR: The software package was shipped with the biorxiv preprint T. Dias-Alves, J. Mairal, and M. Blum. Loter: A Software Package to Infer Local Ancestry for a Wide Range of Species. preprint BiorXiv. 2017

- Participants: Thomas Dias-Alves, Michael Blum and Julien Mairal
- Partners: UGA - CNRS
- Contact: Julien Mairal
- Publication: Loter: A software package to infer local ancestry for a wide range of species
- URL: https://github.com/bcm-uga/Loter

6.4. SPAMS

SPArse Modeling Software

KEYWORDS: Signal processing - Machine learning

FUNCTIONAL DESCRIPTION: SPAMS is an open-source software package for sparse estimation

NEWS OF THE YEAR: The version 2.6.1 of the software package is now compatible with Python v3, R v3, comes with pre-compiled Matlab packages, and is now available on the conda and PyPi package managers.

- Participants: Ghislain Durif and Julien Mairal
- Contact: Julien Mairal
- URL: http://spams-devel.gforge.inria.fr/

6.5. LVO

Learning Video Object Segmentation with Visual Memory

KEYWORD: Video analysis

FUNCTIONAL DESCRIPTION: This is a public implementation of the method described in the following paper: Learning Video Object Segmentation with Visual Memory [ICCV 2017] (https://hal.archives-ouvertes.fr/hal-01511145v2/document).

This paper addresses the task of segmenting moving objects in unconstrained videos. We introduce a novel two-stream neural network with an explicit memory module to achieve this. The two streams of the network encode spatial and temporal features in a video sequence respectively, while the memory module captures the evolution of objects over time. The module to build a "visual memory" in video, i.e., a joint representation of all the video frames, is realized with a convolutional recurrent unit learned from a small number of training video sequences. Given a video frame as input, our approach assigns each pixel an object or background label based on the learned spatio-temporal features as well as the "visual memory" specific to the video, acquired automatically without any manually-annotated frames. The visual memory is implemented with convolutional gated recurrent units, which allows to propagate spatial information over time. We evaluate our method extensively on two benchmarks, DAVIS and Freiburg-Berkeley motion segmentation datasets, and show state-of-the-art results. For example, our approach outperforms the top method on the DAVIS dataset by nearly 6

- Participants: Karteek Alahari, Cordelia Schmid and Pavel Tokmakov
- Contact: Pavel Tokmakov
- Publication: Learning Video Object Segmentation with Visual Memory
- URL: http://lear.inrialpes.fr/research/lvo/

6.6. SURREAL

Learning from Synthetic Humans

KEYWORDS: Synthetic human - Segmentation - Neural networks

FUNCTIONAL DESCRIPTION: The SURREAL dataset consisting of synthetic videos of humans, and models trained on this dataset are released in this package. The code for rendering synthetic images of people and for training models is also included in the release.

- Participants: Gül Varol Simsekli, Xavier Martin, Ivan Laptev and Cordelia Schmid

- Contact: Gül Varol Simsekli

- Publication: Learning from Synthetic Humans

- URL: http://www.di.ens.fr/willow/research/surreal/

6.7. attn2d

Pervasive Attention

KEYWORDS: NLP - Deep learning - Machine translation

SCIENTIFIC DESCRIPTION: Pervasive attention : 2D Convolutional Networks for Sequence-to-Sequence Prediction

FUNCTIONAL DESCRIPTION: An open source PyTorch implementation of the pervasive attention model described in: Maha Elbayad, Laurent Besacier, and Jakob Verbeek. 2018. Pervasive Attention: 2D Convolutional Networks for Sequence-to-Sequence Prediction. In Proceedings of the 22nd Conference on Computational Natural Language Learning (CoNLL 2018)

- Participants: Maha Elbayad and Jakob Verbeek

- Contact: Maha Elbayad

- Publication: Pervasive Attention: 2D Convolutional Neural Networks for Sequence-to-Sequence Prediction

- URL: https://github.com/elbayadm/attn2d

WILLOW Project-Team

6. New Software and Platforms

6.1. NCNet

Neighbourhood Consensus Networks
KEYWORDS: Computer vision - Machine learning
FUNCTIONAL DESCRIPTION: Open source release of the software package for the NIPS'18 paper by Rocco et al. "Neighbourhood Consensus Networks". This release provides a full implementation of the method, including code for training models, and testing on standard datasets, as well as trained models.

- Participants: Ignacio Rocco Spremolla, Mircea Cimpoi, Akihiko Torii, Relja Arandjelovic, Tomas Pajdla and Josef Sivic
- Contact: Ignacio Rocco Spremolla
- Publication: Neighbourhood Consensus Networks
- URL: https://www.di.ens.fr/willow/research/ncnet/

6.2. Mixture-of-Embedding-Experts

KEYWORD: Computer vision
FUNCTIONAL DESCRIPTION: Joint understanding of video and language is an active research area with many applications. Prior work in this domain typically relies on learning text-video embeddings. One difficulty with this approach, however, is the lack of large-scale annotated video-caption datasets for training. To address this issue, we aim at learning text-video embeddings from heterogeneous data sources. To this end, we propose a Mixture-of-Embedding-Experts (MEE) model with ability to handle missing input modalities during training. As a result, our framework can learn improved text-video embeddings simultaneously from image and video datasets. We also show the generalization of MEE to other input modalities such as face descriptors.

- Participants: Ivan Laptev and Josef Sivic
- Contact: Antoine Miech
- Publication: Learning a Text-Video Embedding from Incomplete and Heterogeneous Data
- URL: https://www.di.ens.fr/willow/research/mee/

6.3. BodyNet

BodyNet: Volumetric Inference of 3D Human Body Shapes
KEYWORDS: Computer vision - Machine learning
FUNCTIONAL DESCRIPTION: BodyNet has the code to train multi-task neural networks for 2D/3D pose estimation, 2D body part segmentation, and 3D volumetric shape estimation of human bodies given single RGB images as input. The release also contains pre-trained models.

- Participants: Gül Varol Simsekli, Ivan Laptev and Cordelia Schmid
- Contact: Gül Varol Simsekli
- Publication: BodyNet: Volumetric Inference of 3D Human Body Shapes
- URL: https://www.di.ens.fr/willow/research/bodynet/

6.4. FlexWLoc

Flexible Weakly supervised action Localization model
KEYWORDS: Computer vision - Machine learning

FUNCTIONAL DESCRIPTION: Open source release of the software package for the NIPS'18 paper by Chéron et al. "A flexible model for training action localization with varying levels of supervision". This release provides a full implementation of the method, including code for training and testing.

- Participants: Guilhem Chéron, Jean-Baptiste Alayrac, Ivan Laptev and Cordelia Schmid
- Contact: Guilhem Chéron
- Publication: A flexible model for training action localization with varying levels of supervision
- URL: https://www.di.ens.fr/willow/research/weakactionloc/

6.5. Pinocchio

KEYWORDS: Robotics - Biomechanics - Mechanical multi-body systems
FUNCTIONAL DESCRIPTION: Pinocchio instantiates state-of-the-art Rigid Body Algorithms for poly-articulated systems based on revisited Roy Featherstone's algorithms. In addition, Pinocchio instantiates analytical derivatives of the main Rigid-Body Algorithms like the Recursive Newton-Euler Algorithms or the Articulated-Body Algorithm. Pinocchio is first tailored for legged robotics applications, but it can be used in extra contexts. It is built upon Eigen for linear algebra and FCL for collision detection. Pinocchio comes with a Python interface for fast code prototyping.

- Partner: CNRS
- Contact: JUSTIN CARPENTIER
- URL: https://github.com/stack-of-tasks/pinocchio

6.6. weakalign

End-to-end weakly-supervised semantic alignment
KEYWORDS: Computer vision - Machine learning
FUNCTIONAL DESCRIPTION: Open source release of the software package for the CVPR'18 paper by Rocco et al. "End-to-end weakly-supervised semantic alignment". This release provides a full implementation of the method, including code for training models, and testing on standard datasets, as well as trained models.

- Participants: Ignacio Rocco Spremolla, Relja Arandjelovic and Josef Sivic
- Contact: Ignacio Rocco Spremolla
- Publication: End-to-end weakly-supervised semantic alignment
- URL: https://www.di.ens.fr/willow/research/weakalign/

6.7. InLoc

Indoor Visual Localization with Dense Matching and View Synthesis
KEYWORD: Computer vision
FUNCTIONAL DESCRIPTION: Open source release of the software package for the CVPR'18 paper by Taira et al. "Indoor Visual Localization with Dense Matching and View Synthesis". This release provides a full implementation of the method.

- Participants: Hajime Taira, Masatoshi Okutomi, Torsten Sattler, Mircea Cimpoi, Marc Pollefeys, Josef Sivic, Tomas Pajdla and Akihiko Torii
- Contact: Josef Sivic
- Publication: InLoc: Indoor Visual Localization with Dense Matching and View Synthesis
- URL: https://github.com/HajimeTaira/InLoc_demo